

# Integrated Sensing and Communication Physical Layer Model Documentation

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# Abbreviations

**AP** Access Point.

**BPSK** Binary Phase Shift Key.

**BRP** Beam Refinement Protocol.

**CFO** carrier frequency offset.

**CP** Cyclic Prefix.

**DCM** Dual Carriere Modulation.

**DFT** Discrete Fourier Transform.

**EDMG** Enhanced Directional Multi-Gigabit.

**IDFT** Inverse Discrete Fourier Transform.

**ISAC** Integrated Sensing and Communication.

**LDPC** Low Density Parity Check.

**MCS** Modulation and Coding Scheme.

**mm-wave** millimeter-wave.

**MMSE** Minimum Mean Square Error.

**MSE** Mean Squared Error.

**MU-MIMO** Multi-User Multiple-Input Multiple-Output.

**NMSE** Normalized Mean Squared Error.

**OFDM** orthogonal frequency-division multiplexing.

**PAA** Phased Array Antenna.

**PHY** Physical Layer.

**PPDU** Physical layer Protocol Data Unit.

**QAM** Quadrature Amplitude Modulation.

**QPSK** Quadrature Phase Shift Key.

**RDA** Range-Doppler-Angle.

**SC** single carrier.

**STA** Station.

**STFT** Short-Time-Fourier-Transform.

**SU-MIMO** Single-User Multiple-Input Multiple-Output.

**SU-SISO** Single-User Single-Input Single-Output.

**SVD** Singular Value Decomposition.

**TRN** Training Field.

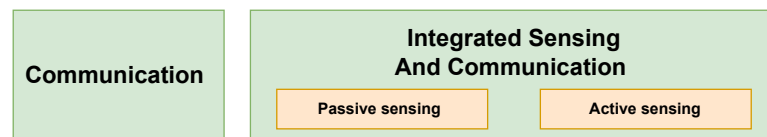
**ZF** Zero Forcing.



# Integrated Sensing and Communication Physical Layer Model Documentation

Integrated Sensing and Communication Physical Layer Model (ISAC-PLM) is an open-source implementation for link level simulation of millimeter-wave (mm-wave) wireless communication and sensing systems. ISAC-PLM includes two different modes (Figure 1):

- A communication mode, modeling the Physical Layer (PHY) of IEEE 802.11ay, including a growing set of features, such as Multi-User Multiple-Input Multiple-Output (MU-MIMO) link level simulation, IEEE 802.11ay [1] single carrier (SC)/orthogonal frequency-division multiplexing (OFDM) waveform generation, synchronization, channel estimation, carrier frequency offset (CFO) estimation and correction.
- An Integrated Sensing and Communication (ISAC) mode, extending the IEEE 802.11ay model to support future wireless systems integrating communication and sensing, such as IEEE 802.11bf [2]. ISAC-PLM introduces micro-Doppler processing to obtain estimation of range, velocity and angles of moving targets using two different techniques:
  - Reusing an IEEE 802.11ay SC/OFDM communication link, extracting sensing information from existing pilot sequences, also known as passive sensing.
  - Transmit dedicated sensing packets, which are used exclusively to perform sensing tasks, also known as active sensing.



**Figure 1:** ISAC-PLM simulates wireless communication or ISAC systems.

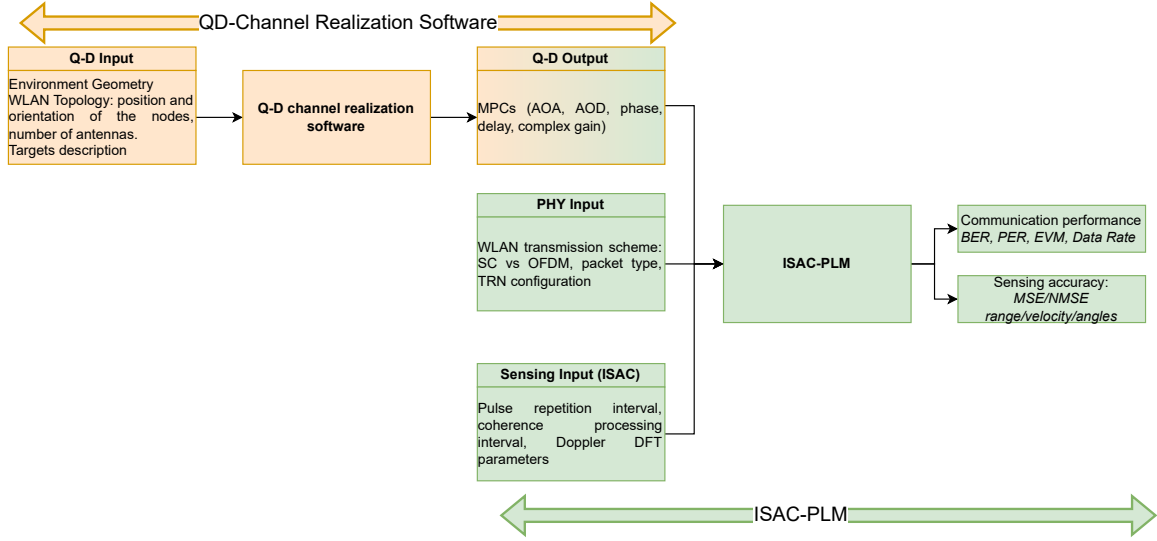


Figure 2: ISAC-PLM workflow.

## 1 Introduction

The ISAC-PLM is part of a collection of tools developed to support both communication systems and ISAC systems design and evaluation [3]. The ISAC-PLM models the end-to-end IEEE 802.11ay PHY processing based on a Matlab implementation<sup>1</sup>. It also extends the communication functionalities with sensing features. Sensing through wireless communication networks aims at utilizing communication signals to detect and sense targets enabling application such as human presence detection, gesture recognition, or object tracking. The ISAC-PLM supports a native integration with the open-source NIST Q-D channel realization software [4] to enable link-level simulations with realistic mm-wave channel models. The ray tracing method used in the NIST Q-D channel realization software, unlike conventional stochastic models, is 3-D environment and transceiver position specific, hence it enables an accurate end-to-end performance evaluation. The NIST Q-D channel realization supports sensing applications evaluation by allowing to simulate channels including moving target.

Figure 2 presents an overview of the ISAC-PLM workflow and its integration with the NIST Q-D channel realization software. The geometry of the environment and the topology of the scenario, e.g., position of the nodes and targets are defined in the NIST Q-D channel realization software. The target coordinates evolution over time are given as input to the Q-D software, which returns the MPCs, both those generated by the interaction of the signal with the target (target related MPCs) and those generated by the interaction between the signal and the environment (target unrelated MPCs). The Q-D output is used as the input of the simulation of the packet transmission.

<sup>1</sup>Requirements: R2021b+, WLAN toolbox

However, ISAC-PLM software usage is not limited to channels generated by the NIST Q-D channel realization software. If the multipath components input provided matches the one expected by the ISAC-PLM (described in Section 4.1.4), one can use as an input of the ISAC-PLM any channel model implementation output or measurement campaigns output.

ISAC-PLM defines as input also parameters to design the digital baseband transmitter and receiver algorithms (PHY input), and it can be configured with a wide range of parameters that define the properties of the communication system and the transceiver settings. For ISAC mode, the sensing processing design is enabled by the Sensing Input, which allows to configure the micro-doppler processing parameters.

At the output of the ISAC-PLM, the following communication metrics are returned:

- Bit Error Rate (BER).
- Packet Error Rate (PER).
- Constellation Error Vector Magnitude (EVM).
- Data Rate.

When using ISAC-PLM in ISAC mode the following sensing metrics are returned:

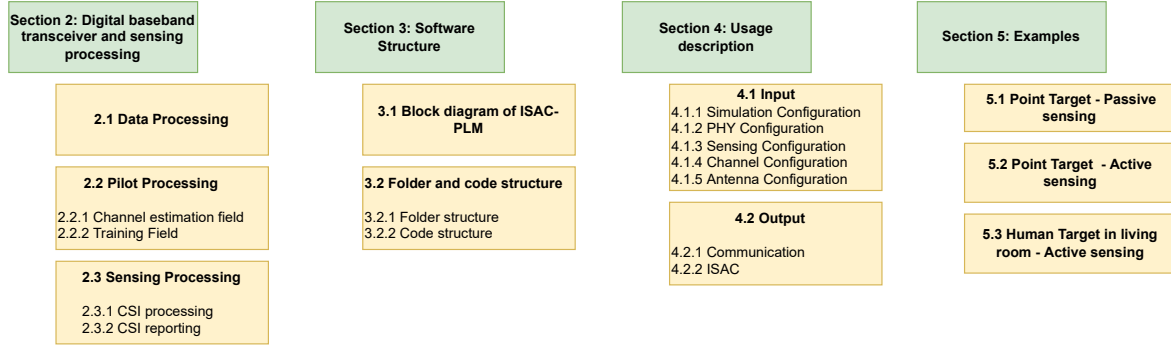
- Histogram of accuracy of detected velocity.
- Histogram of accuracy of detected range.
- Histogram of accuracy of detected azimuth and elevation.
- Sensing accuracy in terms of MSE/NMSE.

The key communication features of the software can be summarized as follows:

- IEEE 802.11ay SC/OFDM waveform generation.
- IEEE 802.11ay spatial multiplexing schemes up to 8 streams: Single-User Single-Input Single-Output (SU-SISO), Single-User Multiple-Input Multiple-Output (SU-MIMO), MU-MIMO.
- Receiver signal processing algorithms: synchronization, channel estimation, carrier frequency offset (CFO) correction.
- Perform link-level bit error rate (BER), packet error rate (PER), data rate tests and analytical link-level spectral efficiency (SE).

The key sensing features of the software can be summarized as follows:

- Sensing signal processing algorithms: clutter removal, Doppler processing, target detection, range, velocity and angle estimation.

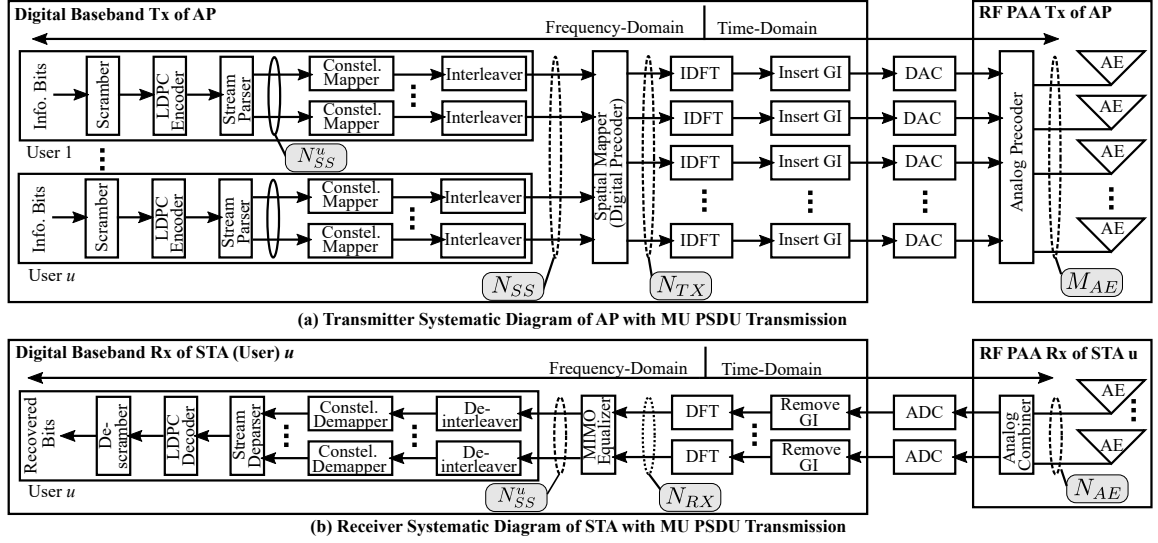


**Figure 3:** Organization of the ISAC-PLM documentation

- Sensing accuracy analysis in terms of Mean Squared Error (MSE) and Normalized Mean Squared Error (NMSE).

The rest of the documentation, depicted in Fig. 3, is organized as follows:

- Section 2 describes the PHY model and gives an overview of the algorithms used both for communication and sensing.
- Section 3 describes the architecture of the software, describing folder, code structure and major functions.
- Section 4 explains how to use the software and the input/output design.
- Section 5 presents some examples.



**Figure 4:** Transceiver diagram of IEEE 802.11ay OFDM mode, in MU-MIMO down-link transmission.

## 2 Digital Baseband Transceiver and Sensing Processor

The digital transceiver extends the IEEE 802.11ad implemented in the MATLAB WLAN toolbox<sup>2</sup> to be IEEE 802.11ay compliant. It supports SU-MIMO and MU-MIMO for both OFDM and SC modes. It also supports several precoder and equalizer options, including Singular Value Decomposition (SVD), Zero Forcing (ZF) precoder, block diagonalized-ZF precoder, and Minimum Mean Square Error (MMSE) equalizer.

The Enhanced Directional Multi-Gigabit (EDMG) frame is made of two main parts: the preamble and the data. The data 2.1 is correctly decoded using the aid of known pilots sequence contained in the preamble 2.2. The proposed digital transceiver can perform synchronization of the received signal, as well as estimating the channel from the Golay pilot sequences provided in the IEEE 802.11ay packet preamble. Moreover, a sensing processor determines the presence of moving target using the evolution of the estimated channel.

## 2.1 Data Processing

Fig. 4 shows the baseband OFDM MU-MIMO signal processing of the EDMG digital transceiver.

As shown in Fig. 4(a), the blocks at the Access Point (AP) transmitter, including scrambler, Low Density Parity Check (LDPC) encoder, stream parser and constellation mapper, are operated on a per user basis; while the remaining processing in the transmit chains, including the spatial mapper, Inverse Discrete Fourier Transform (IDFT), and Cyclic Prefix (CP) insertion, are carried out per digital antenna (or digital chain). The digitally precoded MU-MIMO symbols of each transmit chain are OFDM modulated with a 512 point IDFT, followed by the CP insertion.

The Station (STA) receiver procedure is illustrated in Fig. 4(b). The OFDM symbols are demodulated by Discrete Fourier Transform (DFT) operation followed by the CP removal and a MMSE MIMO equalizer. Subsequently, the constellation demapping, stream deparsing and LDPC decoding are carried out to complete the PHY signal processing procedure. The LDPC encoder and decoder as well as constellation mapper and demapper support a variety of Modulation and Coding Schemes (MCSs) for OFDM mode transmission with different coding rates to comply with the IEEE 802.11ay standard, including Dual Carrier Modulation (DCM)-Binary Phase Shift Key (BPSK), DCM-Quadrature Phase Shift Key (QPSK), 16-Quadrature Amplitude Modulation (QAM), and 64-QAM.

## 2.2 Pilot Sequence Processing

### 2.2.1 Preamble Processing

The preamble contains known pilots sequence, namely Golay sequences, in the legacy short time field (L-STF), in the EDMG-STF, in the legacy channel estimation field (L-CEF) and in the EDMG-CEF. STF and CEF are used in the communication receiver signal processing, for time and frequency synchronizations and channel state information (CSI). These operations are achieved in multiple steps:

- The frame is detected and synchronized by finding the peak of the correlation between the received signal and the known STF pilots.
- Coarse frequency offset is computed by comparing the phase changes into the peaks of the STF correlation.
- Joint frequency offset and channel estimation is performed by correlating the received CEF with the known CEF.

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<sup>2</sup>Certain commercial equipment, instruments, or materials are identified in this paper in order to specify the experimental procedure adequately. Such identification is not intended to imply recommendation or endorsement by the National Institute of Standards and Technology, nor is it intended to imply that the materials or equipment identified are necessarily the best available for the purpose.

### 2.2.2 TRN Processing

At the end of an IEEE 802.11ay Physical layer Protocol Data Unit (PPDU) or in an IEEE 802.11ay Beam Refinement Protocol (BRP) packets, a sequence of Golay sequences can be sent in the Training Field (TRN) to train the receiver and transmitter antenna. IEEE 802.11bf enables the possibility to re-use BRP frames for sensing purposes as well introducing at the time of writing of this documentation, a dedicated multi-static PPDU, also consisting of a sequence of TRN fields.

ISAC-PLM uses a multi-static PPDU to analyze the sensing performance when using directional communications. TRN-R/TRN-T can be precoded using different antenna weight vectors (AWVs), such that the sensing information can be extracted from the channel components that fall into the analog beam created by the selected AWVs.

## 2.3 Sensing Processing

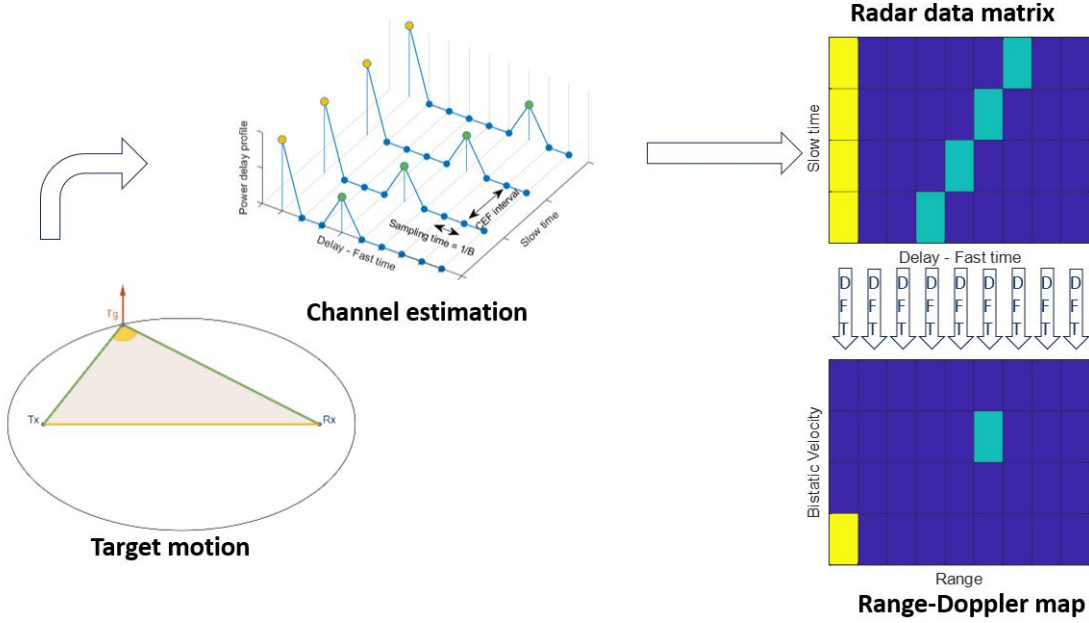
### 2.3.1 CSI processing

ISAC-PLM enables passive sensing for SISO communication links introducing a sensing processor, extracting sensing information from the estimated CSI at the receiver. The CSI, which is already available in the conventional IEEE 802.11ay system, is used to sense the environment by tracking the channel variations over time. Assuming static transmitter and receiver, a perturbation of the CSI can only be caused by a change in the environment, such as a moving target. The sensing processing is executed at the receiver: the receiver, receives the PPDU sent by the transmitter and extract sensing information, beyond being a conventional communication receiver.

From a remote sensing perspective, the channel estimated using the pilot sequences, can be seen as echoes from the targets and the environment. The delays of the echoes from the targets MPCs are proportional to the bi-static distance, i.e. the distance the signal travels from the transmitter to the receiver, scattering out of the target.

ISAC-PLM can perform sensing using a IEEE 802.11ay PPDU or using an IEEE 802.11bf multi-static PPDU.

- Assuming IEEE 802.11ay PPDUs sent continuously over time, with omni antennas, the sensing processor can build the radar data matrix, collecting the estimated CSI (from the preamble) at each packet reception in a 2-dimensional matrix, i.e., the delay (referred also as fast time) and the evolution over the time (referred also as slow time).
- Assuming directional communication, ISAC-PLM precodes the TRN fields, when using a multi-static PPDU. The estimated CSI (from the TRN) is collected in a 3-dimensional matrix including information about the angular domain beyond fast time and slow time.



**Figure 5:** Doppler processing using channel estimation.

To obtain the velocity of the targets, a discrete Fourier transform (DFT) is applied on the slow time dimension of the radar data matrix to allow the estimation of the target speed. A visual representation of the Doppler processing is shown in Figure 5. In case of directional communication with multi-static PPDU, the process is repeated for each transmit-receive AWWs configuration tested.

Null Doppler values in the range-Doppler map, i.e. null velocity, are considered static clutter, i.e., echoes coming from the static environments, thus they are not relevant to the remote monitoring. They can be filtered out, by removing the continuous component along the slow time dimension of the radar data matrix. At the output of the filter only echoes with a non-zero Doppler component are left and these can be associated with motion in the environment.

### 2.3.2 CSI Reporting

ISAC-PLM implements a reporting method defined to minimize the effect of the CSI reporting on the communication.

To minimize the signalling overhead, in the threshold-based sensing measurement and reporting procedure, the sensing receiver feedbacks the CSI only when the estimated CSI variation between successive packets becomes significant. More specifically, the receiver first quantify the CSI variations, comparing the current and previous estimated CSI measurements. If the CSI variation is higher than a threshold, the receiver feedbacks the estimated CSI to the transmitter, otherwise the transmitter reconstruct the missing CSI measurement using interpolation techniques.



This software also supports an adaptive threshold method where the threshold can be adapted to the motion considered. With the adaptive-threshold method the objective is to adjust the CSI-variation threshold dynamically to avoid degrading the sensing performance.

## 3 Software Structure

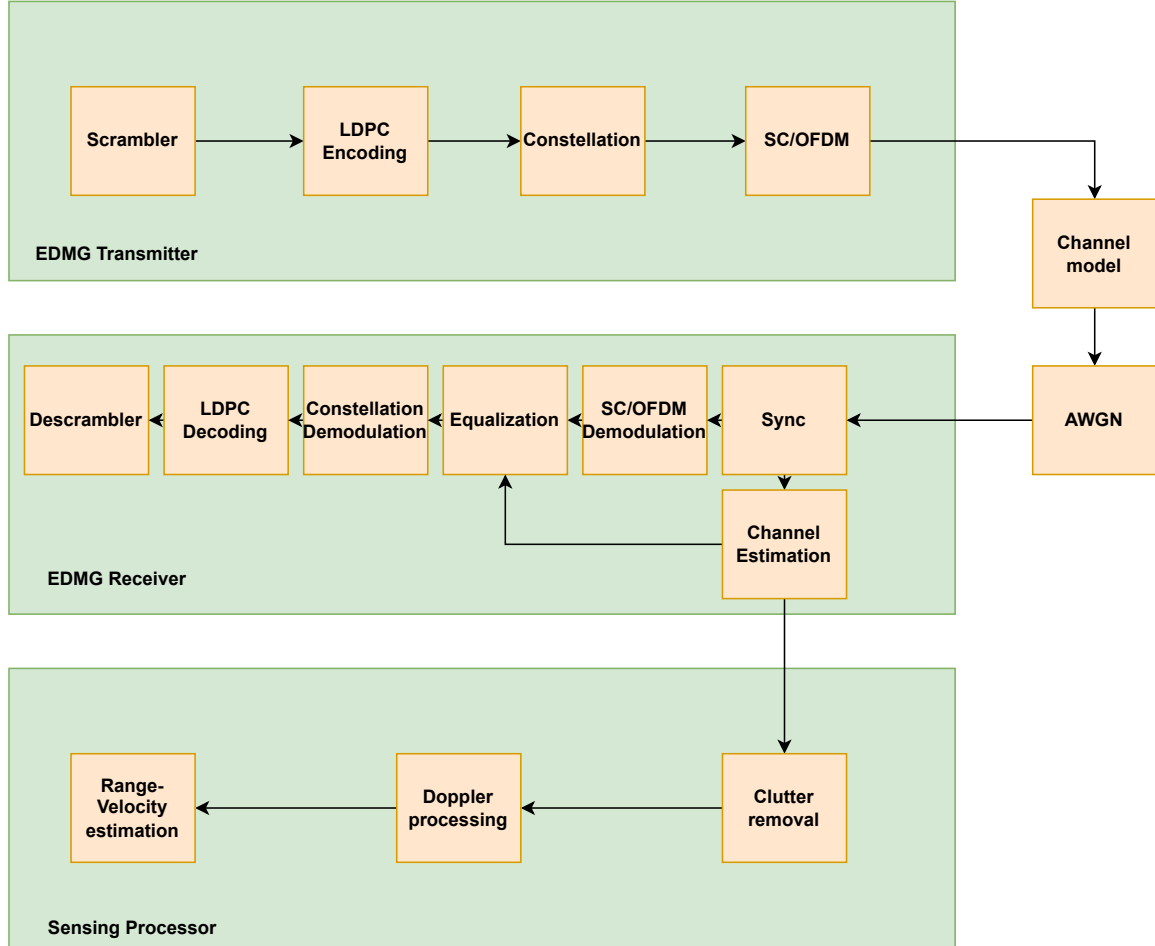
### 3.1 Block Diagram of ISAC-PLM

The ISAC-PLM is organized in three main building blocks: EDMG transmitter, EDMG receiver and in ISAC mode a sensing processor. Figure 6 shows the block diagram of ISAC-PLM with data transmission, i.e. in communication mode or in passive sensing mode:

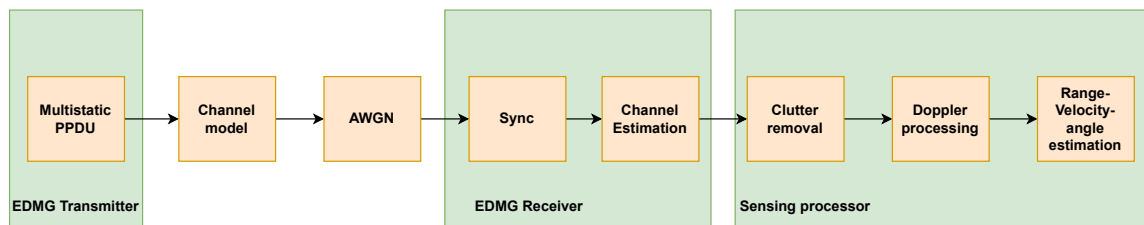
- The EDMG transmitter is in charge to encode randomly generated bits by LDPC, modulate encoded bits to a constellation and apply SC or OFDM modulation to obtain the waveform.
- The EDMG receiver gets in input the waveform passed through the channel model with added white noise. The receiver performs packet by packet synchronization, SC/OFDM demodulation and channel estimation. The channel estimation is used to obtain the equalizer to retrieve the constellation. Demodulation and LDPC decoding allows to retrieve the information bits.
- When using the software in passive ISAC mode, an additional block is considered. The sensing processor uses the channel estimation computed using CEF (IEEE 11ay packet). The channel estimation is first filtered through a clutter removal filter, that eliminates the static background. The Doppler processing returns range-Doppler maps enabling target velocity, range estimation. Target information are obtained finding peaks in the range-Doppler map.

Figure 7 shows the block diagram of ISAC-PLM in active sensing mode, i.e., without data transmission:

- The EDMG transmitter is in charge of generating a dedicated sensing sequence.
- The EDMG receiver processing is simplified performing only synchronization and channel estimation.
- The sensing processor uses the channel estimation computed using TRN. The channel estimation is first filtered through a clutter removal filter, that eliminates the static background. The Doppler processing returns range-Doppler-angle maps enabling target velocity, range and angle estimation. Target information are obtained finding peaks in the range-Doppler-angle map.



**Figure 6:** ISAC-PLM block diagram: communication and passive sensing.



**Figure 7:** ISAC-PLM block diagram: multi-static PPDU for sensing (no data transmission).

## 3.2 Folder and Code Structure

### 3.2.1 Directory Structure

The directory structure is shown in Figure 8. The MATLAB code is located in the folder `isac-plm` containing the main script `main.m` to run the software as a communication link or as an ISAC link. The folder `example` collects predefined configurations. Each of the examples has an `Input` folder defining the configuration files and an `Output` folder that is generated by the ISAC-PLM with the result of the simulation.

The folder `isac-plm\src` contains the Matlab code and includes several sub-folders:

- **channel**: includes the function to generate different channel models, as well as the function to convert the MPCs described in the NIST Q-D channel realization software format to a tapped delay line (TDL) channel model.
- **config**: configuration functions. It includes the files to load the input configuration and set default values.
- **data**: stores data needed to run the software, e.g., angle codebook.
- **ext**: external code files.
- **phy**: link-level simulations functions.
  - `+nist`: MathWorks authored codes revised by NIST.
- **sens**: includes the sensing functions.
- **tools**: includes helper functions.
- **src-antenna-model**: collects the functions to read the angle codebook.

### 3.2.2 Code Structure

The script `main.m` is used to launch the simulation. When the software is used to simulate a communication link `main.m` invokes `runPHYErrorRateDataRate.m` and `runPHYSpectralEfficiency.m` to runs the link-level simulation obtaining BER, PER, data rate and spectral efficiency. When the software is used to simulate an ISAC link, `main.m` invokes `runIsac` to obtain, the sensing accuracy of moving targets. When using ISAC with a conventional IEEE 802.11ay PPDU BER, PER, data rate are also provided.

The ISAC-PLM uses four major structures throughout the implementation. These structures are:

- **simulation**: it contains information about the simulation and the simulator setting. It includes parameter to set noise value, non-idealities, or to enable debug mode or plots.

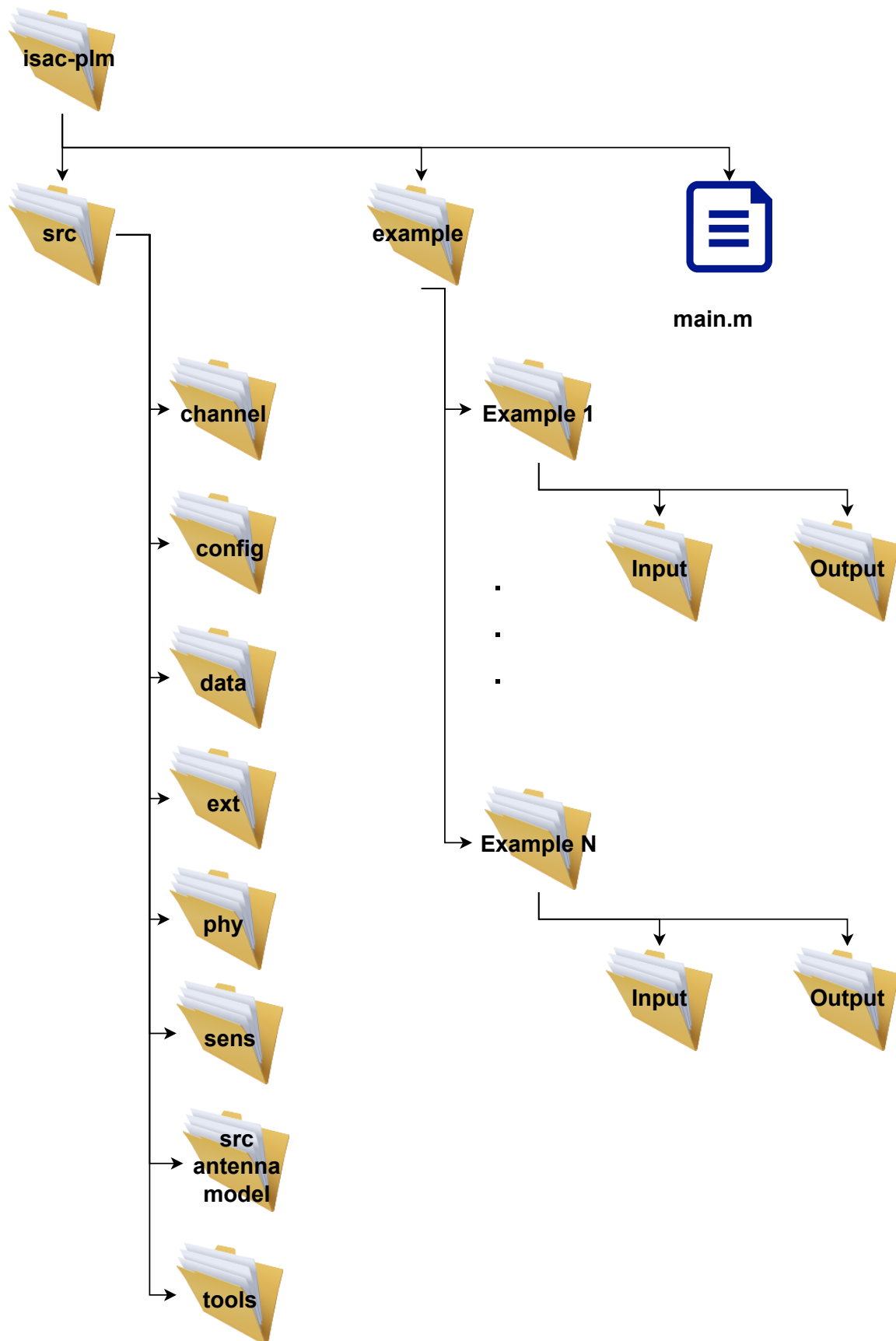


Figure 8: ISAC-PLM folder structure.

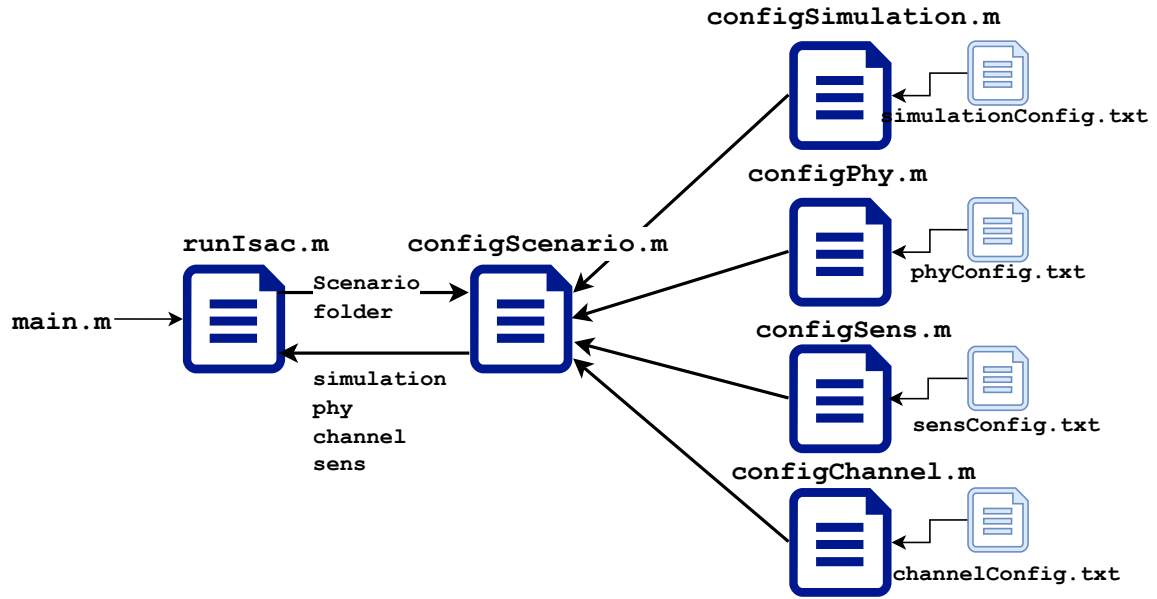


Figure 9: Code structure.

- **phy**: the structure contains all the information relative to the transceiver operation and the algorithms used in the PHY.
- **sens**: this structure is used in ISAC mode and it contains the setting of the sensing processing.
- **channel**: it includes parameters related to the channel model.

These structures are constructed with dedicated configuration files. The configuration files provided as input and described in Section 4.1 are loaded using the functions `configSimulation.m`, `configPhy.m`, `configSens.m` and `configChannel.m`. In case some input parameter is missing in the configuration, these function initializes the parameter to a default value. The code structure is illustrated in Figure 9: the function `runPHYErrorRateDataRate` (for communication) or the function `runIsac` (for ISAC) invokes the `configScenario.m` function passing as input the scenario folder path, containing the configuration files. `configScenario.m` returns in output the Matlab structures used throughout the software.

After loading the configuration the ISAC-PLM uses three main functions implementing the three building blocks shown in Figure 6:

- The function `edmgTx.m` generates the IEEE 802.11ay transmit waveform.
- The function `edmgRx.m` implements the receiver processing.
- In ISAC mode, the function `sensingProcessing.m` implements the sensing processing on the estimated channel state information at the receiver.

## 4 Usage description

This section describes how to setup the ISAC-PLM and how to analyze the results obtained.

### 4.1 Input

The input folder must be properly defined in the scenario folder (for instance, `isac-plm-examples\scenarioFolder\Input`). The configuration is broken down into four configuration files relative to the four main structures used in ISAC-PLM:

- `simulationConfig.txt` (Section 4.1.1).
- `phyConfig.txt` (Section 4.1.2).
- `sensConfig.txt` (Section 4.1.3) - ISAC mode.
- `channelConfig.txt` (Section 4.1.4)

Each file contains in each row a pair parameter-value separated by a tab space. In case of directional transmission using phased antenna arrays (PAAs), an extra file describing the antenna configuration of each node is used (Section 4.1.5).

- `nodePaa<x>.txt`, being `<x>` the index of the node starting from 0.

The input parameters of each file are described in the following and an overview of the accepted parameters is provided in appendix A.

#### 4.1.1 Simulation Configuration

The simulation configuration aims at selecting the properties of the simulation that the users want to analyze and choose the operation mode of the simulator.

The file `simulationConfig.txt` may contain the following fields:

- `debugFlag`: define the software operating mode.  
0 for simulation, 1 for debugging. If the field is not defined `debugFlag` is set to 0.
- `psduMode`: select the packet format.  
0 for PPDU format (header + data), 1 for PSDU format (data-field only).

In communication mode: using the PPDU format, the receiver estimates the channel from the preamble to obtain the channel equalizer. If the field is not defined, `psduMode` is set to 1 and the channel is assumed perfectly known at both transmitter and receiver.

In ISAC mode: `psduMode` is always set to 0, i.e., the channel is estimated (either from CEF or TRN).

- **dopplerFlag**: doppler flag.  
0: Doppler off (block fading). 1: Doppler ON. (Default = 0)
- **snrMode**: SNR definition.  
Ratio of symbol energy to noise power spectral density EsNo, Ratio of bit energy to noise power spectral density EbNo, Signal-to-noise ratio (SNR) per sample SNR. (Default value: EsNo)
- **snrAntNormFlag**: SNR Rx antenna normalization flag.  
0: The receive signal is normalized such that the receive power at each antenna is 1 in average. 1: The receive signal is normalized such that the receive power at each antenna is 1. (Default 0)
- **snrRange**: Simulation SNR range in dB.  
Define the SNR range in dB specified as a 1-by-2 vector of scalar. (Default [0 20])
- **snrStep**: Define the SNR step in dB specified as a positive scalar.  
The simulation SNR points are generated in the range snrRange with a step of snrStep, i.e. snrRange(1):snrStep:snrRange(2). (Default 1)
- **maxNumErrors**: Maximum number of error specified as a positive integer. (Default = 100)
- **maxNumPackets**: Maximum number of packets specified as positive integer. (Default = 1000)

Additional ISAC specific parameters:

- **nTimeSamp**: Number of channel time samples.  
Specify the length in channel samples of the simulation. Each channel sample correspond to a packet transmission. This value must be lower or equal to the number of channel samples in time provided as input (see Channel Configuration).
- **sensPlot**: Save sensing plot.  
Specified as 1 to save the plots otherwise 0 to not save the plots. The plots saved are described in Section 4.2.2.
- **saveRdaMap**: Save Range-Doppler-Angle (RDA) maps  
When setting the saveRdaMap = 1, RDA maps are saved in jpeg files. The plots saved are described in Section 4.2.2. Setting the option **disableRdaAxis** = 1, the jpeg files are saved without axes.

### 4.1.2 PHY Configuration

The PHY configuration defines the properties of the PHY and the algorithms the PHY uses in simulation.

The file `phyConfig.txt` may contain the following fields:

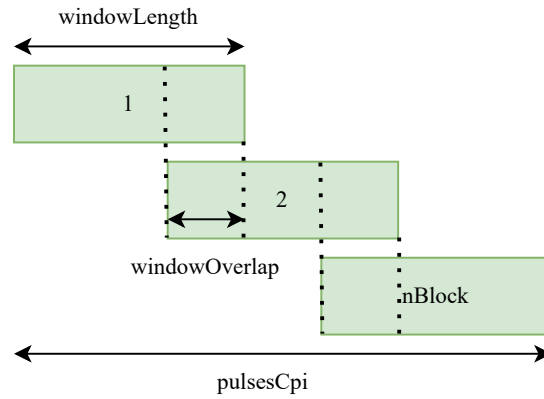
- **phyMode**: PHY mode.  
phyMode is specified as OFDM or SC. (Default OFDM in communication mode, SC in ISAC mode)
- **lenPsdByt**: Length of PSDU.  
lenPsdByt is in byte specifies as positive scalar. (Default = 4096)
- **giType**: Guard interval length.  
giType is specified as Short, Normal or Long.
- **numSTSVec**: Number of downlink spatial-time streams.  
numSTSVec specified as 1-by-STAs vector of positive integers in the range 1-8 such that  $\text{sum}(\text{numSTSVec}) \leq 8$ . (Default = 1) For ISAC, numSTSVec must be set to 1.
- **smTypeNDP**: Spatial mapping type for non-data packet (preamble only, non data-field of PPSU)  
Specified as Hadamard, Fourier, Custom or Direct. (Default is Direct)
- **smTypeDP**: Spatial mapping type for data packet (PSDU, data-field of PPSU).  
smTypeDP specified as Hadamard, Fourier, Custom or Direct. (Default is Direct)
- **mcs**: Modulation and coding scheme (MCS) Index.  
mcs is specified as index in the range 1-20 (21 for SC). (Default = 6).
- **processFlag**: transceiver digital processing flag.  
processFlag selects specific MIMO signal processing for OFDM/SC mode transmitter and receiver. processFlag is specified as a scalar between 0-5 (Default 0).
  - For the transmitter processing,
    - \* processFlag = 0, supports both OFDM and SC SISO and SU-MIMO without transmitter precoding.
    - \* processFlag = 1, OFDM supports SU- and MU-MIMO with frequency-domain precoding based on regularized zero-forcing (RZF) criteria; SC supports SU-MIMO with time-domain one-tap precoding based on RZF criteria.



- \* processFlag = 2, OFDM supports SU-MIMO with frequency-domain precoding based on SVD and RZF filtering; SC supports SU-MIMO with time-domain one-tap precoding based on SVD and RZF filtering.
  - \* processFlag = 3, OFDM supports MU-MIMO with frequency-domain precoding based on SVD and RZF filtering; SC supports SU-MIMO with time-domain one-tap precoding based on SVD and RZF filtering.
  - \* processFlag = 4, OFDM supports SU- and MU-MIMO with frequency-domain precoding based on block diagonalization and ZF filtering (BD=ZF); SC supports SU-MIMO with time-domain one-tap precoding based on BD-ZF.
  - \* processFlag = 5, SC supports MU-MIMO with time-domain multi-tap precoding with ZF.
- For the receiver processing, all processFlag = 0-5 support OFDM/SC joint frequency-domain equalization and MIMO detection based on linear minimum mean squared error (MMSE) criteria.
- **symbOffset**: Symbol sampling offset.  
**symbOffset** is specified as values from 0 to 1. When **symbOffset** is 0, no offset is applied. When **symbOffset** is 1 an offset equal to the GI length is applied. (Default 0.75)
  - **softCsiFlag**: Demodulation with soft channel state information flag.  
**softCsiFlag** is specified as 0 for disabled or 1 for enabled. (Default 1 for OFDM and 0 for SC)
  - **ldpcDecMethod**: LDPC decoding method.  
**ldpcDecMethod** is specified as **norm-min-sum** or **bp**, respectively. (Default **norm-min-sum**)

To configure TRN design when ISAC mode is activated and that Multi-Static PPDU is used:

- **msSensing**: EDMG Multi-Static PPDU structure  
Enable EDMG Multi-Static PPDU structure if set to 1 and channel estimation is obtained using TRN. Otherwise use a EDMG PPDU structure and channel estimation is obtained using CEF.
- **packetType**: Define TRN type  
Define TRN type, specified as ‘TRN-R’ for receiver training, ‘TRN-T’ for transmitter training.



**Figure 10:** Short-Time Fourier transform input arguments

- **trainingLength:** Number of TRN Units  
Indicates the number of TRN Units present in the TRN field of the PPDU.
- **subfieldSeqLength:** Length of subfield sequence (Golay).  
Define the number of samples of the subfield as 128, 256 or 64.
- **unitP:** TRN P sequence  
Value indicated by the EDMG-TRN-Unit P defined as 0,1,2,3.
- **unitM:** TRN M sequence  
Value indicated by the EDMG-TRN-Unit M field.
- **unitN:** TRN N sequence  
Value indicated by the EDMG-TRN-Unit N field.
- **UnitRxPerUnitTx**  
RX TRN-Units per Each TX TRN-Unit.

#### 4.1.3 Sensing Configuration

The sensing configuration aims at defining the parameters used in the sensing processing. The file `sensConfig.txt` may contain the following field:

- **pri:** pulse repetition interval  
Specifies the interval in seconds between each packet as a positive real. Default 0.0005.

- **dopplerFftLen**: Doppler FFT length.  
Specifies the doppler FFT length as a positive integer. Default 64.
- **pulsesCpi**: number of pulses in a coherent processing interval.  
Specifies the number of packets to collect before to compute the doppler FFT. Default 64.
- **window**: FFT window.  
FFT window specified as `rect`, `hamming`, `blackmanharris`, `gaussian`. Default `rect`.
- **windowLen**: Short-Time-Fourier-Transform (STFT) window length  
Split data before doppler FFT in overlapping windows of length **windowLen** (Figure 10). Default 64.
- **windowOverlap**: STFT window overlap  
Specifies the percentage of the window overlapping between 0 and 1 (Figure 10). Default 0 (no overlap).

Optional for threshold-based sensing:

- **thresholdSensing**: enables threshold-based sensing measurement and reporting procedure to analyze the sensing performance. Default = 0.
- **adaptiveThreshold**: activates adaptive thresholding for threshold based sensing. Default = 0.
- **numTimeDivisions**: specifies the number of time-divisions for which the threshold has to be adaptively calculated. This is valid only for `adaptiveThreshold = 1`. Default = 5.
- **threshold**: specifies the threshold value used for threshold based sensing. In case adaptive threshold is activated i.e., `adaptiveThreshold = 1`, this specifies the initial threshold. Default = 0.
- **stepThreshold**: specifies the step size for threshold. This is valid only for `adaptiveThreshold = 1`. Default = 0.1.
- **percentMeasurement**: specifies the percent of the measurements expected by the node for sensing processing. This is valid only for `adaptiveThreshold = 1`. Default = 90.
- **csiVariationScheme**: defines the CSI variation scheme used for threshold based sensing. The software currently supports `EucDistance`, `TRRS`, and `FRRS`. This is valid only for `thresholdSensing = 1`. Default = `TRRS`.

- `interpolationScheme`: defines the interpolation scheme used for missing measurement in threshold based sensing. The software currently supports `previousMeasurement`, `linearInterpolation`, and `zeroPadding`. This is valid only for `thresholdSensing = 1`. Default = `previousMeasurement`.

#### 4.1.4 Channel Configuration

The channel configuration specifies the properties of the channel over which the packets are transmitted.

- In communication mode, several channel models can be used, such as AWGN, Rayleigh or Q-D models.
- To evaluate the performance of an ISAC system, any channel model or measurements provided in the format of the NIST Q-D channel realization model can be used.

The channel model is configured with the file `channelConfig.txt`. The file `channelConfig.txt` must contain the field `chanModel`. When using ISAC-PLM in communication mode, the field `chanModel` must be specified as:

- AWGN
- Rayleigh
- NIST

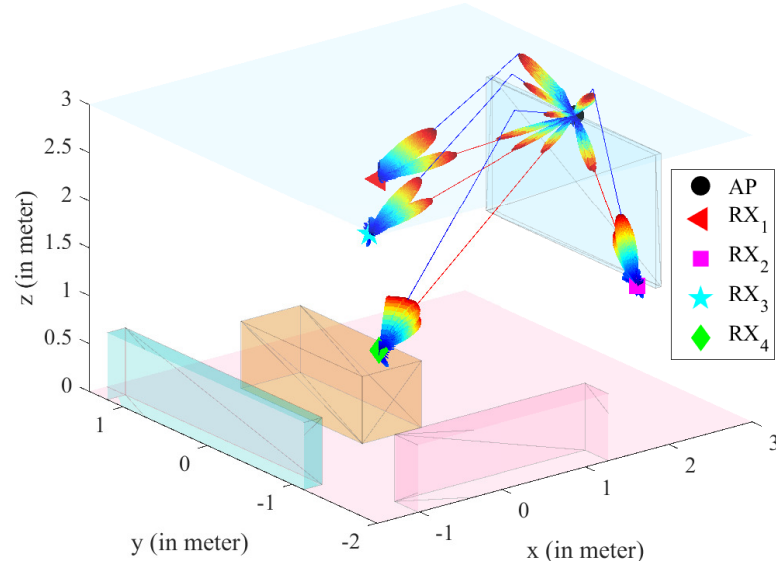
When using ISAC-PLM in sensing mode, the field `chanModel` must be specified as:

- Sensing

The labels `NIST` refers to a dataset of channels obtained using the Q-D channel realization software. To use `NIST` please contact the authors for the additional dataset. As the configuration of each channel model might have different parameters the file `channelConfig.txt` contains different fields according with the channel model selected.

#### AWGN

To use an AWGN channel it is enough to specify the property `chanModel` as `AWGN` in the configuration file `channelConfig.txt`.



**Figure 11:** Indoor Q-D channel model for a living room scenario and spatial filtering provided by analog beam-steering of Phased Array Antenna (PAA).

### Rayleigh Channel Parameter Configuration

The file `channelConfig.txt` may contain the following fields:

- **numTaps:** Number of channel taps.  
Number of channel taps specified as a positive integer. If the field is not defined `numTaps` is set to 10.
- **pdpMethodStr:** Power delay profile for tapped-delay line (TDL) channel model.  
`pdpMethodStr` is specified as `PS`, `Equ` or `Exp`, using phase shift, equal power or exponential power, respectively.
- **tdlTypeChannel** Interpolation Method of CIR.  
`tdlTypeChannel` is specified as `Impulse` or `Sinc`.(Default `Impulse`)

### NIST Q-D Channel Parameter Configuration

The ISAC-PLM provides a dataset of system level channels obtained using the NIST-QD channel realization software and provided upon requests. After ray tracing, the MPCs are filtered through a Phased Array Antenna (PAA) antenna model and analog beamforming algorithms. The system level channels can be provided for different indoor and outdoor environments as well as for different PAA models and analog beamforming schemes. Figure 12 shows a living room environment and the spatial filtering on the MPCs provided by the analog beamforming.

The file `channelNistConfig.txt` loading one of the predefined channel, may contain the following fields that allows to load the correct dataset:

- `environmentFileNamechannel` `environmentFileNamechannel` is specified as LR for lecture room, OAH for open area hotspot or SC for street canyon. If the field is not defined `environmentFileName` is set to LR.
- `totalNumberOfReflections`: Reflection order. `totalNumberOfReflections` is specified as a positive integer. If the field is not defined `totalNumberOfReflections` is set to 2.
- `tdlTypeChannel` Interpolation Method OF TDL CIR filtering. `tdlTypeChannel` is specified as Impulse or Sinc.

Moreover, the antenna model can be configured for each node in the system thanks to the file `paaConfigNodeX.txt` where X represents the node index from 0. `paaConfigNodeX.txt` may contain the following fields:

- `numAntenna`: Total number of antenna element in the node.  
`numAntenna` is specified as a positive integer. If the field is not defined `numAntenna` is set to 16.
- `Geometry`: Geometry of the antenna array.  
`Geometry` is specified as `UniformLinear` or `UniformRectangular`.
- `numAntennaVert`: Total number of antenna element in the vertical direction.  
`numAntennaVert` is specified as a positive integer. If the field is not defined `numAntennaVert` is set to 4.

## Sensing

ISAC-PLM provides a native integration with the Q-D channel realization output format specifying the property `chanModel` as `sensing` in the configuration file `channelConfig.txt`.

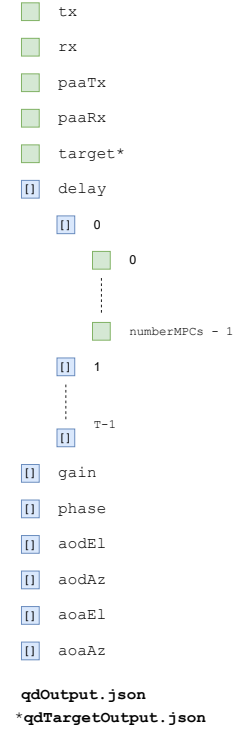
The folder `Input\sensingChannel` must include the file `qdOutput.json` and may include the file `qdTargetOutput.json`, both described in Figure 12. Each row of the file describes a combination transmitter-transmitter paa-receiver- receiver paa. Each row includes the following fields:

- delay (s)
- gain (dB)
- phase (rad)
- AOD EL (deg), AOD AZ (deg)
- AOA EL (deg), AOA AZ (deg)

Each of these fields is a vector of length  $T$ , i.e., the number of channel samples. Moreover, each time sample entry is a vector describing the properties at each MPC. The file `qdOutput.json` contains the description of all the MPCs of the channel. The file `qdTargetOutput.json`, contains only the information of a single MPC per target (specified by the `target` field), which can be assumed as the reference to compute ground truth velocity, range and angles. The ground truth information it is used to provide accuracy metrics of detection. In case the file `qdTargetOutput.json` error analysis is not provided. An example on how to use the ISAC-PLM together with the Q-D channel realization software is provided in Section 5.1.

The file `channelConfig.txt` may contain the following fields:

- **normalization**: normalization of the channel. Normalization of the channel specified as `packet` for a per packet normalization of the channel or `none` to avoid any normalization.



**Figure 12:** Channel Input: `qdOutput.json` and `qdTargetOutput.json`

### 4.1.5 Antenna configuration

When simulating directional propagation in active sensing mode, the antenna pattern and the direction of the antenna steering defined by the antenna wave vector, need to be taken into account. ISAC-PLM provides a set of predefined angular codebooks, specifying the array steering vectors and the antenna wave vectors.

The antenna pattern has one main beam which is steered to a particular direction. The entries of the angle-based codebook define the possible steering directions of the PAA. The provided codebooks are relative to rectangular PAA of different sizes:

- $2 \times 8$ : 2 vertical antennas, 8 horizontal antennas.  
Codebook Azimuth: [0 11 23 34 45 56 68 79 90 270 281 292 304 315 326 337 349]  
Codebook Elevation: [0 45 90 135 180]
- $4 \times 8$ : 4 vertical antennas, 8 horizontal antennas.  
Codebook Azimuth: [0 11 23 34 45 56 68 79 90 270 281 292 304 315 326 337 349]  
Codebook Elevation: [0 22 45 67 90 113 135 158 180]
- $8 \times 8$ : 8 vertical antennas, 8 horizontal antennas.  
Codebook Azimuth: [0 11 23 34 45 56 68 79 90 270 281 292 304 315 326 337 349]  
Codebook Elevation: [0 11 22 33 45 56 67 78 90 101 112 123 135 146 157 168 180]

The file `nodePaa<x>.txt` loading one of the predefined channel, may contain the following fields that allows to load the correct codebook:

- Codebook: specify the angle-based codebook.  
Select the PAA dimension and load the angle-based codebook. Specified as one of the codebooks provided: 'cb2x8.txt', 'cb4x8', 'cb8x8'. `cbRxC` refers to a rectangular PAA with R rows and C columns. The files `nodePaa<x>.txt` are optional for isotropical transmission. The files `nodePaa<x>.txt` may be defined for directional transmission. `nodePaa0.txt` refers to the AP. `nodePaa1.txt` refers to the STA.

## 4.2 Output

ISAC-PLM provides as output the results of the link-layer simulation and the results of the sensing accuracy.



### 4.2.1 Communication output

The evaluation of the communication system is provided in terms of BER, PER, EVM and data rate, while an ISAC system is evaluated also in terms of the sensing accuracy, hence, velocity and range MSE and NMSE are provided.

The results of the simulation are stored in `isac-plm\examples\exampleFolder\Output`. The file `isac-plm-ws.mat` stores the following information:

- `berIndiUser`: BER for each individual user.
- `perIndiUser`: PER for each individual user.
- `evmIndiUser`: EVM expressed in dB for each individual user.
- `berAvgUser`: Average BER among users.
- `perAvgUser`: Average PER among users.
- `evmAvgUser`: Average EVM among users.
- `gbitRateIndiUser`: Data rate for each individual user.
- `gbitRateAvgUser`: Average data rate for each individual user.
- `gbitRateSumUser`: Sum data rate.

### 4.2.2 Sensing output

In case of an ISAC simulation ISAC-PLM provides in `isac-plm\examples\scenarioFolder\Output\Sensing` the results in JSON format. Three files are provided:

#### **sensingInfo.json**

`sensingInfo.json`: stores variable relative to time and velocity scale as well as ground truth information of range and velocity.

- `axVelocity`: vector of velocities bins expressed in m/s. The length is `dopplerFftLen`.
- `axFastTime`: vector of delay bins relative to sync point expressed in s. The length of the vector is `maxDelayBin`.
- `timeOffset`: time offset expressed in s to map the relative fast time `axFastTime` into an absolute temporal scale `axAbsFastTime` as `axAbsFastTime = axFastTime + timeOffset`.
- `axDopFftTime`: vector of slow time bins at which the Doppler FFT is computed, expressed in s.

- **axPri**: vector of slow time bins expressed in s.
- **gtRange**: ground truth range expressed in m.
- **gtVelocity**: ground truth velocity expressed in m/s.
- **gtAz**: ground truth azimuth expressed in deg.
- **gtEl**: ground truth elevation expressed in deg.

Optional output for threshold based sensing:

- **normCSIVarValue**: normalized CSI variation values for threshold-based sensing.
- **threshold**: fixed or adaptive threshold values.

### **targetInfo.json**

**targetInfo.json**: stores variable relative to the estimated target information such as range, velocity and angles:

- **snr**: SNR
- **targetId**: Target ID.
- **rangeEstimate**: range estimation expressed in m.
- **velocityEstimate**: velocity estimation expressed in m/s.
- **angleAzEstimate**: velocity estimation expressed in deg.
- **angleElEstimate**: velocity estimation expressed in deg.

### **rda.json**

**rda.json**: stores the denoised range-Doppler-angle map. The denoised range-Doppler-angle map is a sparse matrix, hence only the  $N$  non-zero elements of the matrix are saved. The file includes the subscripts corresponding to the velocity, range and angle vectors defined in **sensingInfo.json**:

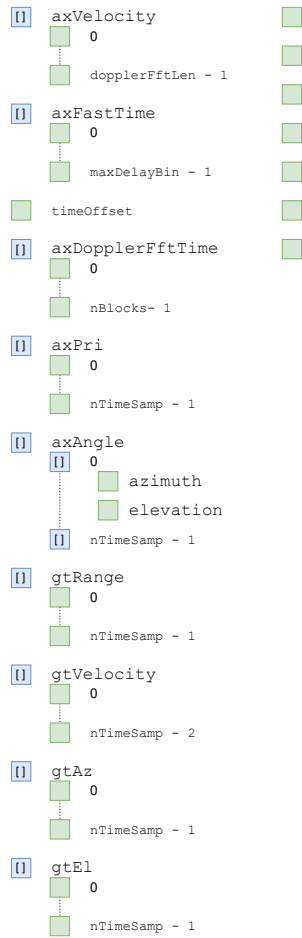
- **snr**: SNR
- **dopplerFftId**: index identifying the FFT block processed at the time corresponding to the **dopplerFftIdth** entry of the vector **axDopFftTime**.
- **axisRange**: range indices of the  $N$  non-zero entries of the RDA matrix. Range value can be retrieved from the vector **axFastTime**.

- **axisVelocity**: velocities indices of the  $N$  non-zero entries of the RDA matrix. Velocities value can be retrieved from the vector `axVelocity`.
- **axisAngle**: angle indices of the  $N$  non-zero entries of the RDA matrix. Angles value can be retrieved from the vector `axAngle`.
- **reflectionPower**: Value in linear scale of the  $N$  non-zero entries of the RDA matrix.

### **sensingResults.json**

**sensingResults.json**: stores the sensing accuracy, estimated range and doppler and the raw range doppler map:

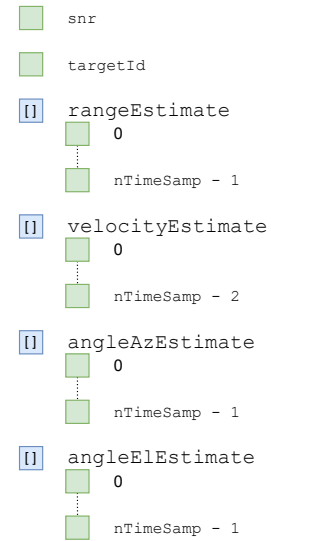
- **snr**: SNR
- **rangeNMSEdB**: NMSE range expressed in dB scale.
- **velocityNMSEdB**: NMSE velocity expressed in dB scale.
- **rangeMSEdB**: MSE range expressed in dB scale.
- **velocityMSEdB**: MSE velocity expressed in dB scale.



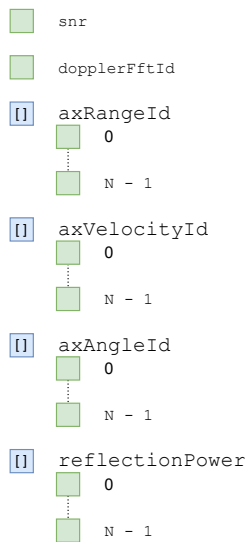
(a) sensInfo.json



(b) sensResults.json



(c) targetInfo.json



(d) rda.json

Figure 13: Sensing Output.

### Sensing Plot

In case of an ISAC simulation, ISAC-PLM can provide output plots in `\Output-\Sensing\Figures` by setting the field `sensPlot = 1` in `configSimulation.txt`. The following plots are provided in .fig format:

- Range-Doppler map (Fig. 14a). The Range-Doppler map is plot for each `dopplerFftId` as a subplot of the figure.
- Micro-Doppler (Fig. 14b): evolution of the velocity over time.
- Range vs time (Fig. 14c): evolution of the range over time.

If ground truth information is provided (see Section 4.1.4):

- Histogram of velocity estimation accuracy (Fig. 15a).
- Histogram of range estimation accuracy (Fig. 15b).

When using active sensing mode (`msSensing= 1` in `phyConfig.txt`):

- Azimuth-elevation maps. The azimuth-elevation map is plot for each `dopplerFftId` as a subplot of the figure (Fig 16a).
- Azimuth vs time (Fig 16b).
- Elevation vs time (Fig 16c).

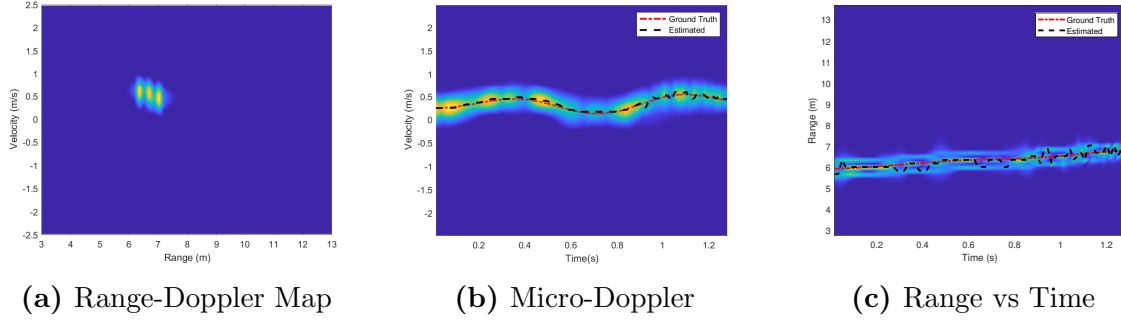
When using active sensing mode, if ground truth is provided:

- Histogram of azimuth estimation accuracy.
- Histogram of elevation estimation accuracy.

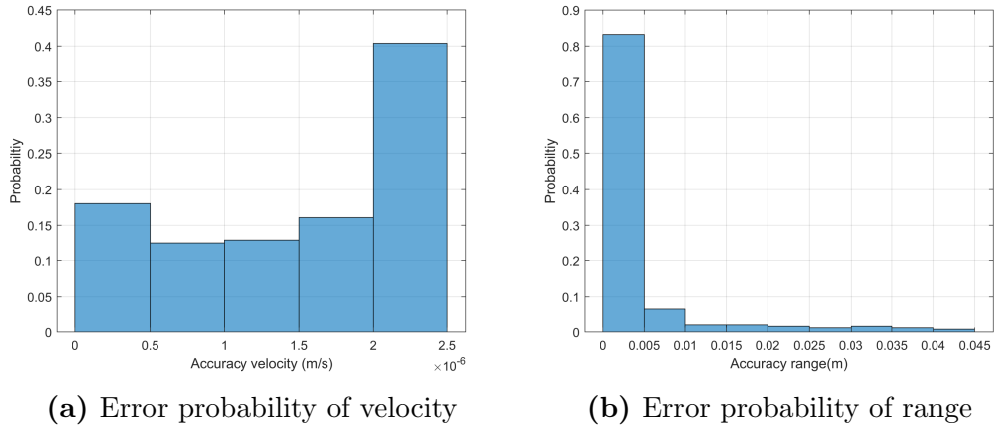
Optional plots for threshold based sensing:

- Normalized CSI variation vs time: variation of normalized CSI variation with respect to time.
- Number of measurements vs threshold: number of measurements required to feedback for varying threshold. Also, provides the number of measurements required to feedback for a threshold considered in the simulation.

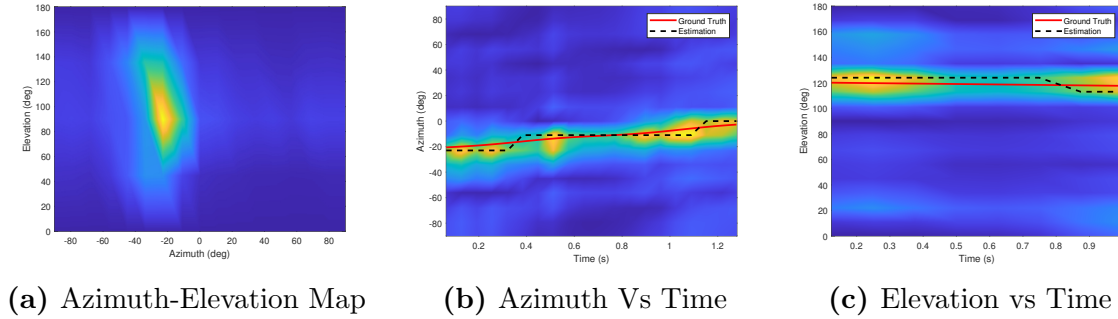
When setting `saveRda = 1` jpeg files of the 2D plots extracted from the 3D RDA are saved as shown in Figure 17.



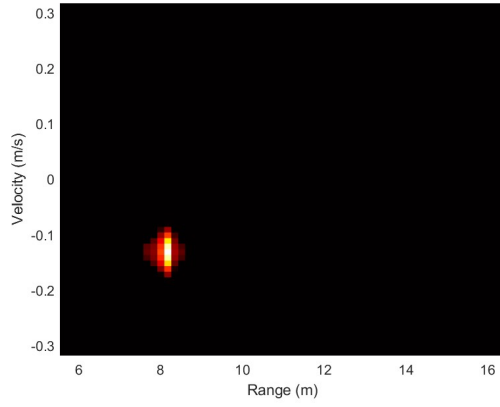
**Figure 14:** Sensing plot output.



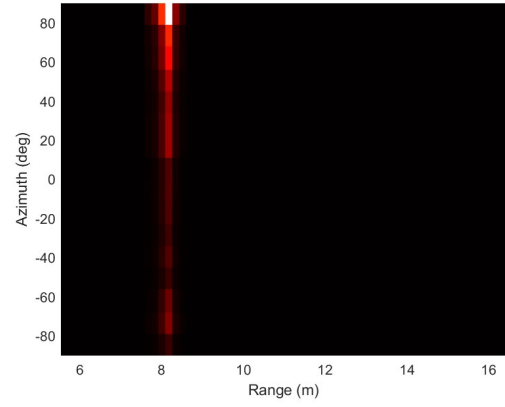
**Figure 15:** Sensing plot output if ground truth is provided.



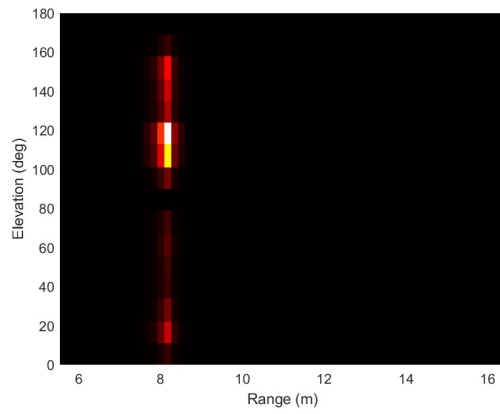
**Figure 16:** Sensing plot output when using active sensing.



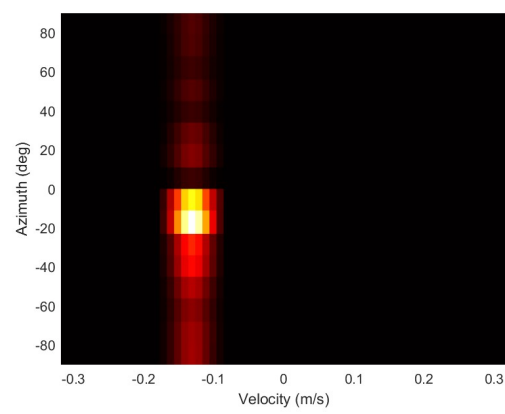
(a) Range-Doppler Map



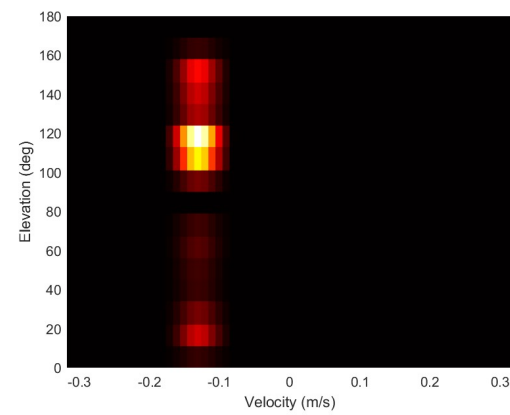
(b) Azimuth-Range Map



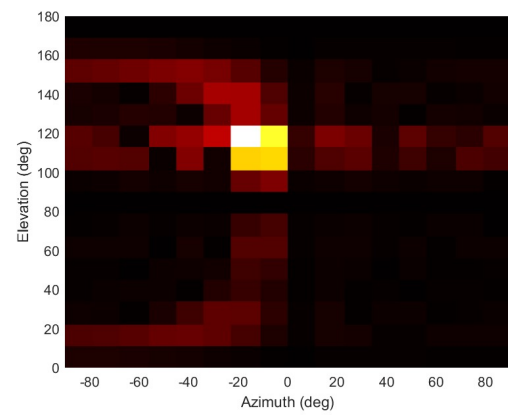
(c) Elevation-Range



(d) Azimuth-Velocity



(e) Elevation-Velocity



(f) Elevation-Azimuth

**Figure 17:** Sensing plot setting `saveRda = 1`.

## 5 Examples

The following example demonstrate how to use the tools provided in [3] to simulate an ISAC system.

To follow these examples simply checkout both Q-D channel realization software and ISAC-PLM in `yourfolder\`.

The folder structure will be as follow:

- `yourfolder\qd-realization`
- `yourfolder\isac-plm`

### 5.1 Point Target in Empty Room - Passive Sensing

This example (`isac-plm\examples\pointTargetPassiveSensing`) starts with the configuration of the NIST QD channel realization software. A single dimensionless point target moving is ray traced between one transmitter and one receiver in a 3-D empty room. The ray traced multipath components provide a deterministic channel model, which is specific for the trasmitter and receiver location, the environment and the motion of the target analyzed. The channel model is used as input configuration of ISAC-PLM to simulate a SISO-SC ISAC link.

The input configuration and the output results are already provided, however in the following, a step-to-step tutorial is provided to re-design the example by using Matlab. The configuration of the software can be obtained also with other tools, since the input parameters are stored in text files.

#### 5.1.1 Deterministic Channel Model

The Q-D channel configuration folder of the Point Target example is already provided in `qd-realization\src\examples\PointTarget`.

To re-create the Point Target example, generate a new input folder in which the configuration files will be added:

```
exampleFoler = '<>\qd-realization\src\examples\NewPointTarget';
inputFolder = ([exampleFolder , '\Input']);
mkdir(inputFolder)
```

### 3-D Scenario Configuration

- Specify the indoor 3-D map in XML format.

In the example folder `qd-realization\src\examples\PointTarget\Input` an empty living room of dimension  $7 \times 7 \times 3$  m is provided in `LivingRoom.xml`,



however a custom map can be created. For a tutorial on how to create a custom map, please refer to [4], otherwise just paste the provided file.

- Specify the nodes position in `NodePositionX.dat`

The SU-SISO link is composed by two nodes, one transmitter and one receiver. The transmitter (node 0) is placed at (-3.9,0,2.8)m while the receiver (node 1) is placed at (3,0,2.8) m.

The configuration files can be written as:

```
writematrix([-3.9,0,2.8],[inputFolder,\'NodePosition0.dat'])
writematrix([3,0,2.8],[inputFolder,\'NodePosition1.dat'])
```

- Specify the point target trajectory in `TargetBase0.dat`

The target is moving over time, hence a list of 3-D coordinates need to be provided. In this example a linear motion is used and it can be generated as:

```
x = linspace(-1, 0, 512)';
y = linspace(-1, 0, 512)';
z = linspace(1, 1, 512)';
writematrix([x,y,z], [inputFolder,\'TargetBase0.dat'])
```

- Specify the parameter configuration of the Q-D channel realization software in `paraCfgCurrent.txt`.

The Q-D is configured to generate 256 channel realization in the indoor living room map provided. The channel is configured to have a single reflection order from the environment and the target rays are not interacting with the environment (no target ghost on the reflecting surfaces of the environment). The total motion is assumed to be 2 seconds. The integration with the ISAC-PLM is enabled by writing the QD channel realization software in JSON format and by returning the target rays.

```
%Environment file
cfg.ParameterName{1,1} = 'environmentFileName';
cfg.ParameterValue{1,1} = 'LivingRoom.xml';

%Number of channel realization to generate
cfg.ParameterName{2,1} = 'numberOfTimeDivisions';
cfg.ParameterValue{2,1} = 256;
```

```
%Environment reflection order
cfg.ParameterName{3,1} = 'totalNumberOfReflections';
cfg.ParameterValue{3,1} = 1;

%Target reflection order
cfg.ParameterName{4,1} = 'totalNumberOfReflectionsSens';
cfg.ParameterValue{4,1} = 0;

%Simulation time in seconds
cfg.ParameterName{5,1} = 'totalTimeDuration';
cfg.ParameterValue{5,1} = 2;

%Output file format
cfg.ParameterName{6,1} = 'outputFormat';
cfg.ParameterValue{6,1} = 'json';

%Store a dedicated target MPC file
cfg.ParameterName{7,1} = 'writeTRayOutput';
cfg.ParameterValue{7,1} = 1;

%Write phase of MPCs
cfg.ParameterName{8,1} = 'enablePhaseOutput';
cfg.ParameterValue{8,1} = 1;

%Write Configuration File
writetable(struct2table(cfg), ...
[inputFolder, '\paraCfgCurrent'], "FileType", 'text',...
'delimiter', '\t')
```

## Ray tracing

To perform the ray tracing:

- Open `main.m` in `yourfolder\qd-realization\src`
- Set `scenarioNameStr = 'examples\NewPointTarget'`
- Run `main.m`

### 5.1.2 ISAC system and signal processing

The ISAC-PLM configuration example is provided in `\isac-plm\examples\PointTarget`.

To re-create the Point Target example, generate a new input folder in which the configuration files will be added:

```
plmExampleFolder = '\isac-plm\examples\NewPointTarget';
inputFolder = ([plmExampleFolder , '\Input']);
mkdir(inputFolder)
```

### ISAC configuration

- Specify the PHY configuration in `phyConfig.txt`

Configure a SC SU-SISO communication link that uses a 16-QAM.

```
% Set SC mode
cfgPhy.ParameterName{1,1} = 'phyMode';
cfgPhy.ParameterValue{1,1} = 'SC';

% Set SISO
cfgPhy.ParameterName{2,1} = 'numSTSVec';
cfgPhy.ParameterValue{2,1} = 1;

% Set MCS
cfgPhy.ParameterName{3,1} = 'mcs';
cfgPhy.ParameterValue{3,1} = 12;

% Write Configuration File
writetable(struct2table(cfgPhy), ...
[inputFolder, '\phyConfig'], "FileType", 'text',...
'delimiter', '\t')
```

- Specify the sensing configuration in `sensConfig.txt`.

Configure the sensing processor to use range-doppler processing using an FFT length of 64 and for a CPI of 64. No STF overlap is used in this example and no data windowing.

```
% Set pulse repetition interval
cfgSens.ParameterName{1,1} = 'pri';
cfgSens.ParameterValue{1,1} = 0.0005;

% Set FFT-length for doppler processing
cfgSens.ParameterName{2,1} = 'pri';
cfgSens.ParameterValue{2,1} = 256;

% Set FFT-window for doppler processing
cfgSens.ParameterName{3,1} = 'pri';
cfgSens.ParameterValue{3,1} = 'rect';
```

```
% Set FFT-window lenght
cfgSens.ParameterName{4,1} = 'windowLen';
cfgSens.ParameterValue{4,1} = 64;

% Set FFT-window overlap
cfgSens.ParameterName{5,1} = 'windowOverlap';
cfgSens.ParameterValue{5,1} = 0;

% Set CPI
cfgSens.ParameterName{6,1} = 'pulsesCpi';
cfgSens.ParameterValue{6,1} = 64;
```

- Specify the simulation setting in `simulationConfig.txt`

Set the simulator to transmit 256 complete packets (data+preamble) with an SNR of 20 dB.

```
% Use preamble in packet transmission
cfgSim.ParameterName{1,1} = 'psduMode';
cfgSim.ParameterValue{1,1} = 0;

% Define length of the simulation
cfgSim.ParameterName{2,1} = 'nTimeSamp';
cfgSim.ParameterValue{2,1} = 256;

% Define SNR
cfgSim.ParameterName{3,1} = 'snrRange';
cfgSim.ParameterValue{3,1} = 20;

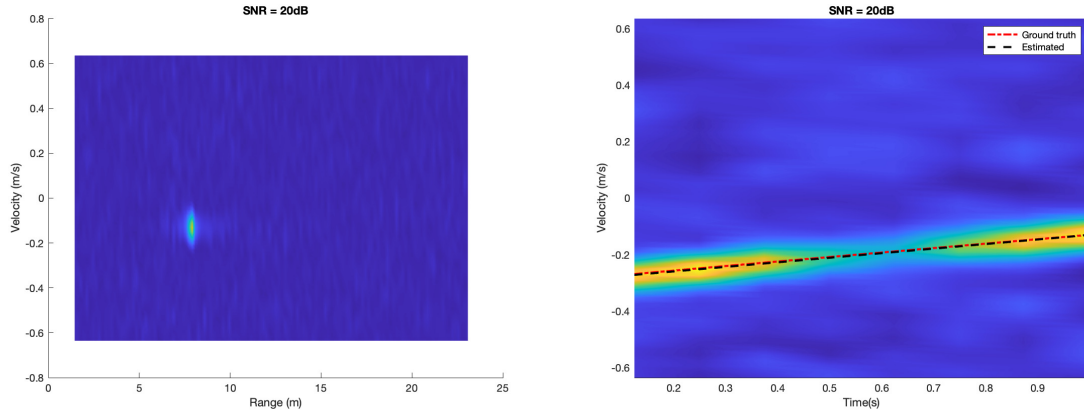
% Write Configuration File
writetable(struct2table(cfgSim), ...
[inputFolder, '\simulationConfig'], "FileType", 'text',...
'delimiter', '\t')
```

- Channel configuration in `channelConfig.txt`

Configure the ISAC-PLM to read the output of the Q-D channel realization software:

```
cfgChan.ParameterName{1,1} = 'chanModel';
cfgChan.ParameterValue{1,1} = 'sensing';

% Write Configuration File
writetable(struct2table(cfgChan), ...
[inputFolder, '\channelConfig'], "FileType", 'text',...
'delimiter', '\t')
```



**Figure 18:** Point target sensing results.

- Copy Q-D output to ISAC-PLM input

Copy the Q-D output (`qdOutput.json` and `qdTargetOutput.json`) to the ISAC-PLM input folder `isac-plm\examples\NewPointTarget\Input\qdChannel`.

### ISAC simulation

To perform the isac simulation:

- Open `mainIsac.m` in `yourfolder\isac-plm\src`
- Set `scenarioNameStr = 'examples\NewPointTarget'`
- Run `mainIsac.m`

### ISAC results

Beyond the output files stored in `\Output`, several figures are available in `\Output\Sensing\Figures` for a quick interpretation of the sensing results. Figure 18 shows the range doppler map and the micro-doppler. The range doppler map on the left, shows a single peak that correspond to the velocity and range of the target. The micro-doppler on the right shows the variation of the detected velocity over time.

## 5.2 Point Target in Empty Room - Active Sensing

In this example (`isac-plm\examples\pointTargetActiveSensing`) a single dimensionless point target is moving between one transmitter and one receiver in a 3-D empty room, as in the previous example. To simulate a directional ISAC link uses the TRN design of a multistatic PPDU proposed for IEEE 802.11bf. Assuming TRN-R, i.e., training at the receiver an  $8 \times 8$  phased antenna array, while the transmitter uses an omni antenna, ISAC-PLM must be configured as follows.

### Configuration of the channel input

Define the file `channelConfig.txt` specifying the channel model used.

- Specify the channel model: `chanModel sensing`

Define the folder `qdChannel` including the files:

- `qdOutput`. This file include the channel MPCs
- `qdTargetOutput`. This file includes a single MPC per target, which is considered as the reference for computing target related information (such as, velocity, range and angle) and it is used to compute results and statistics of the designed system.

### Configuration of the receiver antenna pattern

Define the file `nodePaa1.txt` specifying the antenna model among the models in `isac-plm\src\data`. In this example an  $8 \times 8$  phased antenna array is provided. This codebook includes 289 directions, combination of 17 azimuth and 17 elevation directions. To configure the file `nodePaa1.txt`:

- Specify the codebook name: `Codebook cb8x8.txt`

### TRN-R design to scan the codebook

Define the file `phyConfig.txt`, enabling the multistatic PPDU and specifying the design of the TRN-R. To configure the file `phyConfig.txt`:

- Enable the multistatic PPDU: `msSensing 1`
- Specify the type of TRN: `packetType TRN-R`
- Specify the golay length: `subfieldSeqLength 128`.
- Define the training length to support 289 directions: `trainingLength 29`.

### Doppler Processing Design

Define the file `sensConfig.txt` to use a coherent process interval of 32 packets. The Doppler FFT of length 64 is executed pre-filtering the data with a Blackman-Harris window and without the use of STFT. The pulse repetition interval in seconds, is dictated by the channel sampling rate (see previous section). To configure the file `sensConfig.txt`:

- Define PRI: `pri 0.0039`
- Set FFT window as the number of pulses per CPI: `windowLen 32, pulsesCpi 32`

- Set window overlap: `windowOverlap 0`.
- Specify Doppler FFT length: `dopplerFftLen 64`
- Specify the the pre-FFT window: `window blackmanharris`

### Define Simulation parameters.

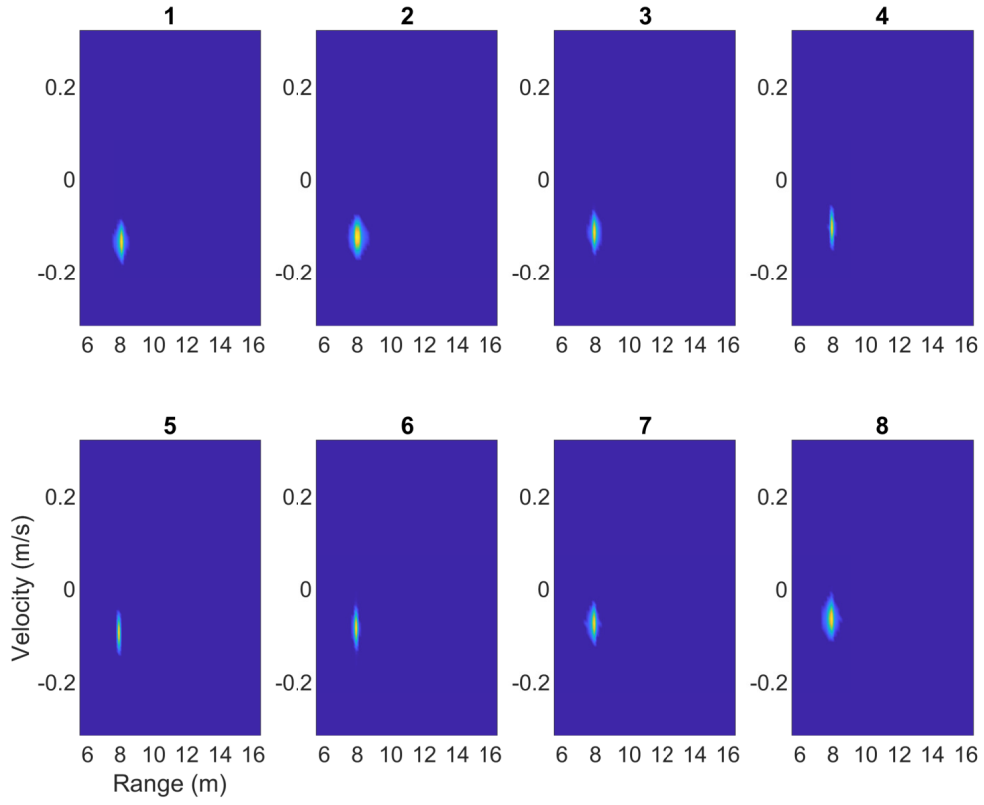
Define the length of the simulation in number of channel samples. In this example the maximum length allowed by the channel provided in the input is considered. The transmission is noise free. The sensing plot are provided in output as well as the 2D images extracted from the 3D RDA map. To configure the file `simulationonfig.txt`:

- Specify the length of the simulation in number of channel samples: `nTimeSamp 256`.
- Specify the SNR in dB: `snrRange 300`.
- Save sensing plot and 2D RDA images as: `sensPlot 1 saveRdaMap 1`

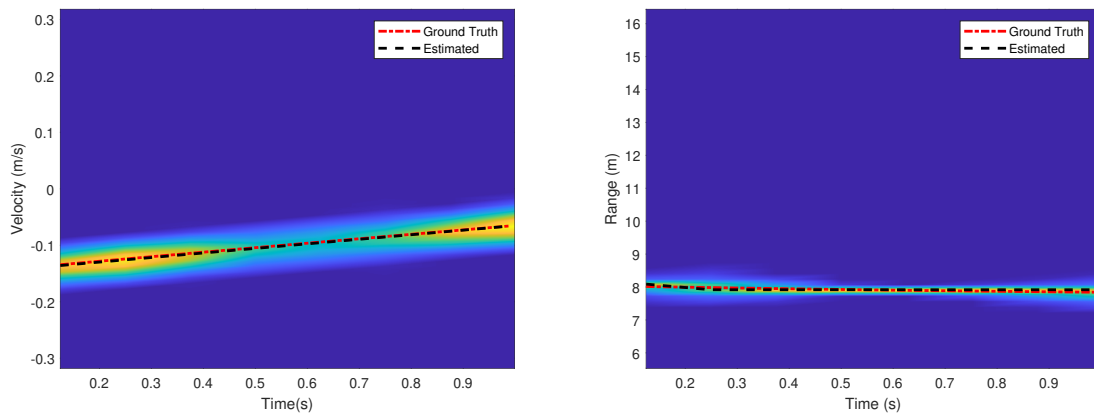
### Output

Beyond the output files stored in `\Output`, several figures are available in `\Output\-\Sensing\Figures` for a quick interpretation of the sensing results.

- Figure 19 shows the Range-Doppler map evolution over the slow time. Since 256 packets have been transmitted and a CPI of 32 packets has been considered,  $256/32 = 8$  RD maps are provided as subplots of the same figure, correspondent to each Doppler FFT.
- Figure 20 shows the velocity vs time and the range vs time maps. The estimated target information and the ground truth information is provided.
- Since ground truth information are provided, ISAC-PLM returns the performance of the designed system. Figure 21 shows the performance in terms of error probability of velocity and range.
- Since multi-static PPDU is used to sense towards multiple directions, ISAC-PLM returns angular information. Figure 22 shows the angle of arrival azimuth and elevation map over the slow time. 8 angular maps are provided as subplots of the same figure, correspondent to each Doppler FFT.
- Figure 23 shows the azimuth vs time and the elevation vs time maps. The estimated target information and the ground truth information are provided.
- Since ground truth information are provided, ISAC-PLM returns the performance of the designed system in the angular domain. Figure 24 shows the performance in terms of error probability of azimuth and elevation.

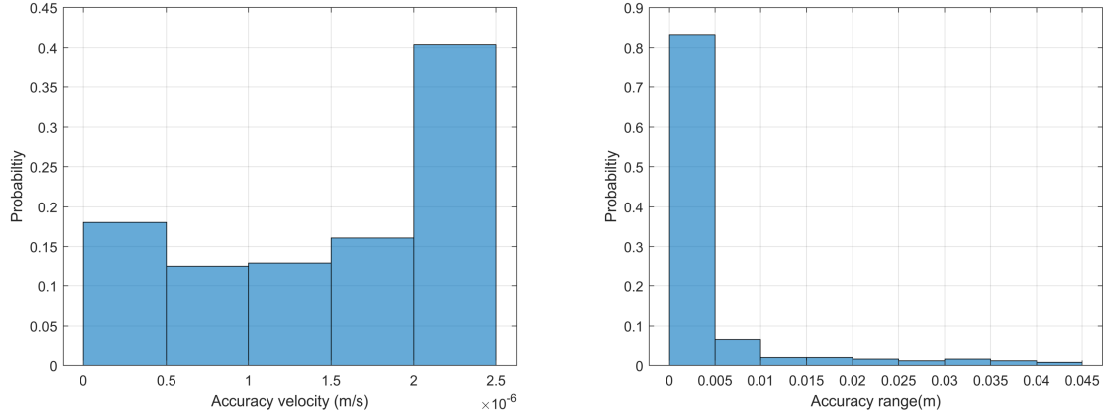


**Figure 19:** RD maps evolution over the slow time

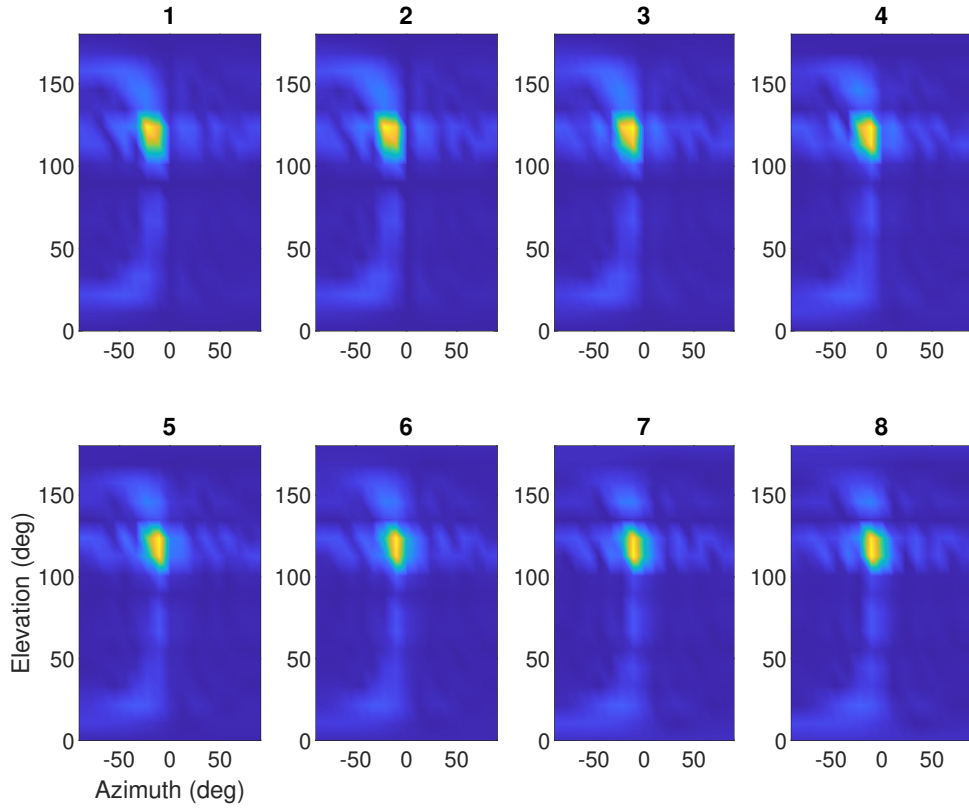


**Figure 20:** Velocity and range evolution over time.

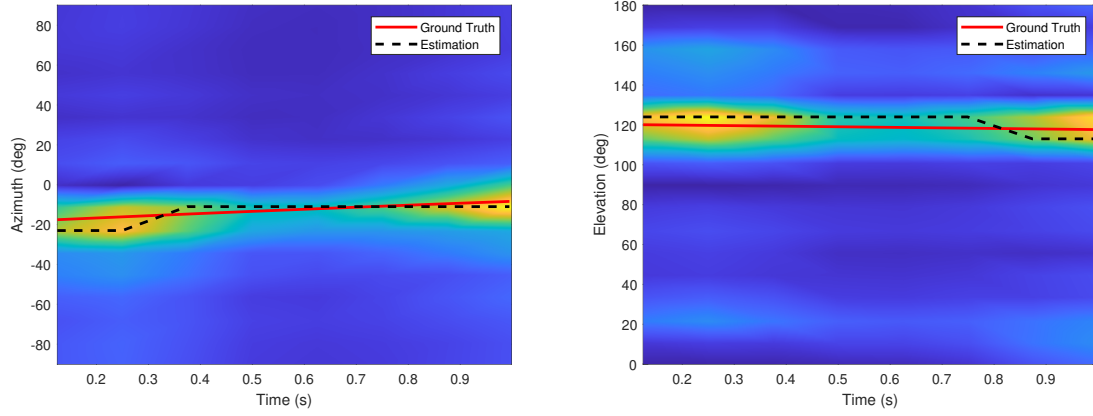




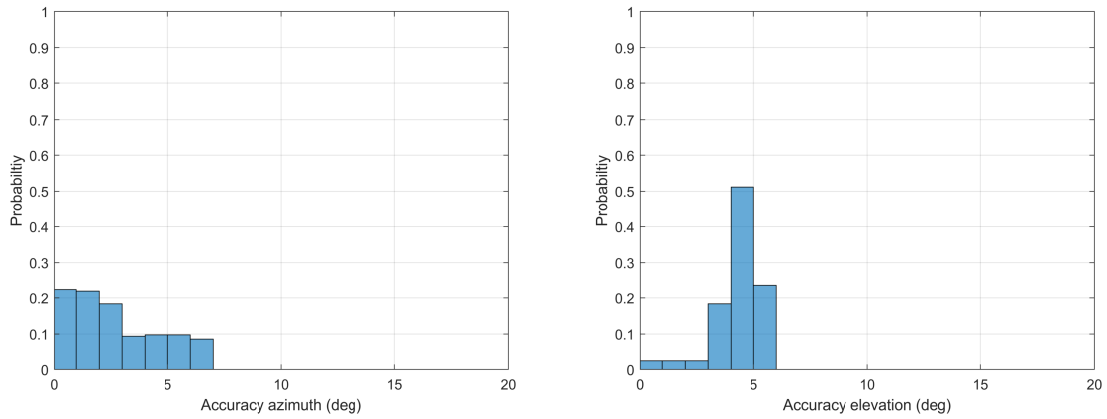
**Figure 21:** Sensing results in terms of error probability of velocity and range estimation.



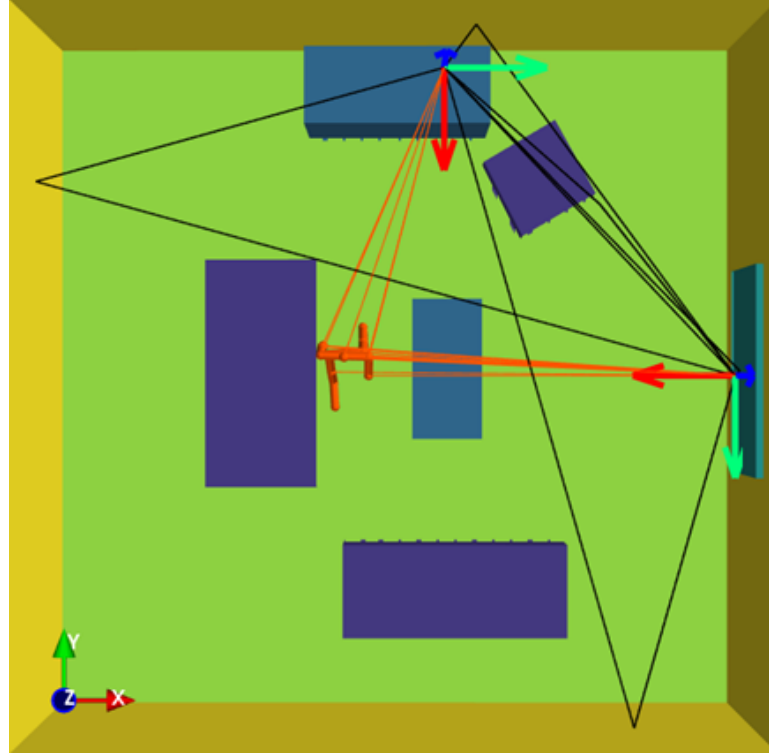
**Figure 22:** Azimuth-Elevation maps evolution over the slow time



**Figure 23:** Azimuth/Elevation estimation over time.



**Figure 24:** Sensing results in terms of error probability of azimuth and elevation estimation.



**Figure 25:** Human target in living room.

### 5.3 Human Target in Living Room - Active Sensing

In this example (`isac-plm/examples/bistaticLivingRoomTRN-T`) a human target composed by dimensionless points (boulic model [5]) is moving between one transmitter and one receiver in a living room, which includes furniture as in Figure 25. To simulate a directional ISAC link uses the TRN design of a multistatic PPDU proposed for IEEE 802.11bf. Assuming TRN-T, i.e., training at the transmitter an  $2 \times 8$  phased antenna array, while the receiver uses an omni antenna, ISAC-PLM must be configured as follows.

#### Configuration of the channel input

As in Section 5.2.

#### Configuration of the receiver antenna pattern

Define the file `nodePaa0.txt` specifying the antenna model among the models in `isac-plm/src/data`. In this example an  $2 \times 8$  phased antenna array is provided. This codebook includes 85 directions, combination of 17 azimuth and 5 elevation directions. To configure the file `nodePaa1.txt`:

- Specify the codebook name: `Codebook cb8x8.txt`

### **TRN-T design to scan the codebook**

Define the file `phyConfig.txt`, enabling the multistatic PPDU and specifying the design of the TRN-R. To configure the file `phyConfig.txt`:

- Enable the multistatic PPDU: `msSensing 1`
- Specify the type of TRN: `packetType TRN-T`
- Specify the golay length: `subfieldSeqLength 128`.
- Define the training length to support 85 directions:
  - `unitP 2`.
  - `unitM 15`.
  - `unitN 1`.

### **Doppler Processing Design**

As in Section 5.2.

### **Define Simulation parameters.**

As in Section 5.2.

### **Output**

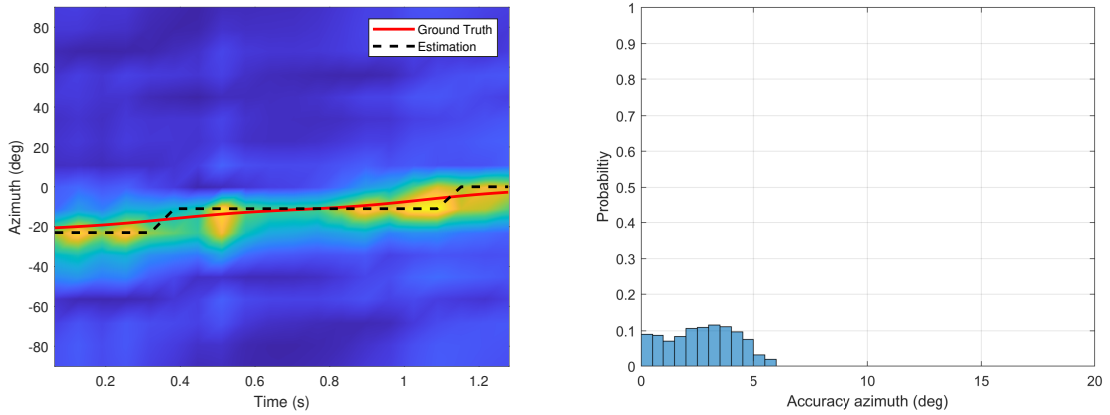
Similar plot as in Section 5.2 are found in the output folder. As an example, Figure 26 shows the angle of departure azimuth estimation and the azimuth error probability.

## **5.4 Threshold-based Sensing Measurement and Reporting**

In this example (`isac-plm\examples\thresholdSensing`) movement of a human target composed by dimensionless points (bouluc model [5]) is considered. To demonstrate the impact of threshold-based sensing measurement and reporting, we considered a transmitter and receiver pair with omni-directional antenna. ISAC-PLM must be configured as follows.

### **Configuration of the channel input**

As in Section 5.2.



**Figure 26:** Human target in living room angle of departure azimuth estimation and azimuth error probability

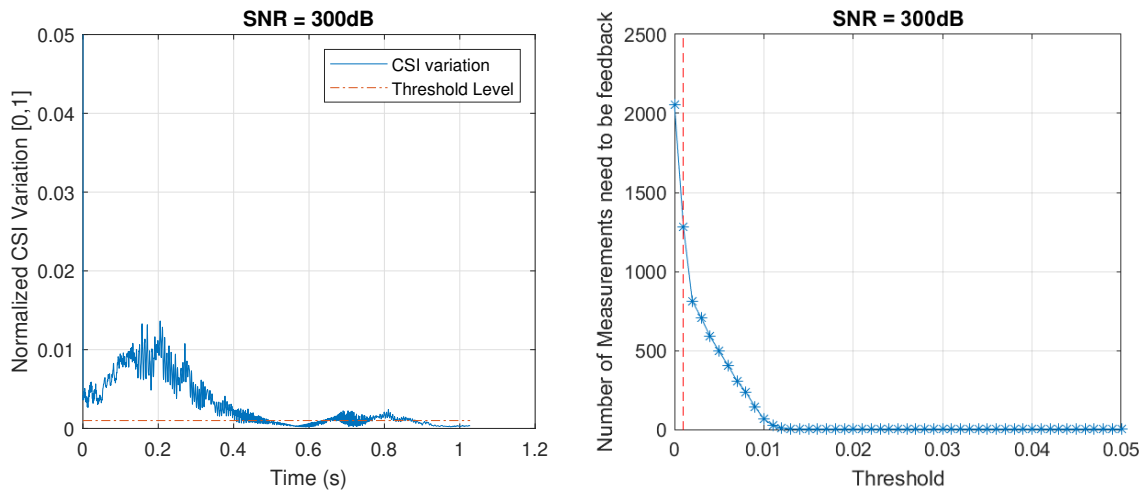
### Doppler Processing Design

Define the file `sensConfig.txt` to use a coherent process interval of 64 packets. The Doppler FFT of length 64 is executed pre-filtering the data with a Hamming window and with the use of STFT, as described in Fig. 10. The pulse repetition interval in seconds, is dictated by the channel sampling rate (see the previous section). To configure the file `sensConfig.txt`:

- Define PRI: `pri 0.0005`
- Set FFT window length: `windowLen 16,`
- Set the number of pulses per CPI: `pulsesCpi 64`
- Set window overlap: `windowOverlap 0.1.`
- Specify Doppler FFT length: `dopplerFftLen 64`
- Specify the pre-FFT window: `window hamming`
- Specify the thresholdSensing: `thresholdSensing 1`
- Specify the threshold: `threshold 0.001`
- Specify the csiVariationScheme: `csiVariationScheme TRRS`
- Specify the interpolationScheme: `interpolationScheme linearInterpolation`

### Define Simulation parameters.

As in Section 5.2.



**Figure 27:** Normalized CSI variation versus time and number of measurements need to be feedback from the receiver.

## Output

All the output results can be found in the output folder. For your reference, normalized CSI variation over time and number of measurements need to be feedback from the receiver are given in Fig. 27.

# Appendix A

## List of Input Parameters

**Table A.1:** Tunable properties of simulation in `simulationConfig.txt`.

Parameter	Description	Data Type	Valid Range	Default
<code>debugFlag</code>	Enables debug mode	double	{0, 1}	0
<code>psduMode</code>	Packet type	double	{0, 1}	1, 0*
<code>dopplerFlag</code>	Enables Doppler effect	double	{0, 1}	0
<code>snrMode</code>	SNR definition	char — string	‘EsNo’, ‘EbNo’	‘EsNo’
<code>snrAntNormFlag</code>	SNR normalization	double	{0, 1}	0
<code>snrRange</code>	SNR range	1-by-2 double	Positive Values	[0 20]
<code>snrStep</code>	SNR step	double	Positive integer	1
<code>maxNumErrors</code>	Max number of errors	double	Positive integer	100
<code>maxNumPackets</code>	Max number of packets	double	Positive integer	1000
<code>nTimeSamp*</code>	Channel time samples	double	Positive integer	32
<code>plotSens*</code>	Plot range doppler	double	{0, 1}	0

\*ISAC

Table A.2: Tunable properties of phy in phyConfig.txt.

Parameter	Description	Data Type	Valid Range	Default
phyMode	PHY mode	char — string	‘OFDM’, ‘SC’	‘OFDM’
lenPsdByt	Length of PSDU.	double	positive scalar	4096
giType	Guard Interval Type	char — string	‘Short’, ‘Normal’, ‘Long’	‘Long’
numSTSVec	Num. spatial-time streams	double	Integer in [1,8]	1
smTypeNDP	Spatial Mapping Pilots	char — string	‘Hadamard’, ‘Fourier’, ‘Custom’, ‘Direct’	‘Direct’
smTypeDP	Spatial Mapping Data	char — string	‘Hadamard’, ‘Fourier’, ‘Custom’, ‘Direct’	‘Direct’
mcs	Modulation-Coding Index	double	Integer in [0,20-21]	6
processFlag	Transceiver mode	double	Integer in [0,5]	1
symbOffset	Symbol sync offset	double	Real in [0,1]	0.75
softCsiFlag	Soft CSI	double	{0, 1}	0 (SC), 1 (OFDM)
ldpcDecMethod	LDPC decoding method	char — string	‘norm-min-sum’, ‘bp’	‘norm-min-sum’
msSensing	Multi-Static PPDU	Double	0,1	1
packetType	Type of TRN in MS-PPDU	char — string	‘TRN-R’, ‘TRN-T’	‘TRN-R’
trainingLength	EDMG TRN Length	Double	Integer in [0-255]	30
subfieldSeqLength	TRN Subfield Sequence Length	Double	128,256, 64	128
unitP	EDMG TRN-Unit P	Double	0,1,2,4	2
unitM	EDMG TRN-Unit M	Double	Integer in [0-15]	1
unitN	EDMG TRN-Unit N	Double	Integer in [1 2 3 4 8]	1
UnitRxPerUnitTx	RX TRN-Units per Each TX TRN-Unit	Double	Integer in [0-255]	54



**Table A.3:** Tunable properties of `sens` in `sensConfig.txt`.

Parameter	Description	Data Type	Valid Range	Default
<code>pri</code>	Pulse Repetition Interval	double	positive scalar	0.0005
<code>dopplerFftLen</code>	FFT length	double	positive integer	64
<code>pulsesCpi</code>	Coherent Pulses	double	positive integer	64
<code>window</code>	FFT window	double	positive integer	64
<code>windowLen</code>	FFT window length	double	positive integer	64
<code>windowOverlap</code>	FFT window overlap	double	Real in $[0,1]$	0
<code>thresholdSensing*</code>	Threshold-based sensing	double	Real in $[0,1]$	0
<code>adaptiveThreshold*</code>	Adaptive threshold	double	Real in $[0,1]$	0
<code>numTimeDivisions*</code>	Number of time-divisions	double	positive integer	5
<code>threshold*</code>	Threshold	double	Real in $[0,1]$	0
<code>stepThreshold*</code>	threshold step size	double	Real in $[0,0.5]$	0.1
<code>percentMeasurement*</code>	percent of measurements	double	Real in $[0,100]$	90
<code>csiVariationScheme*</code>	CSI variation scheme	char-string	EucDistance, TRRS, FRRS	TRRS
<code>interpolationScheme*</code>	Interpolation scheme	double	previous-Measurement, linearInterpolation, zeroPadding	previous-Measurement

\*Optional for threshold based sensing.

**Table A.4:** Tunable properties of `chan` in `channelConfig.txt` if `chanModel = Rayleigh`.

Parameter	Description	Data Type	Valid Range	Default
<code>numTaps</code>	Number of taps	double	positive scalar	10
<code>pdpMethodStr</code>	Power delay profile	char — string	PS, Equ, Exp	Exp
<code>tdlTypeChannel</code>	Interpolation	char — string	Impulse, Sinc	Impulse

**Table A.5:** Tunable properties of `chan` in `channelConfig.txt` if `chanModel = NIST`.

Parameter	Description	Data Type	Valid Range	Default
<code>environmentFileNameChannel</code>	Environment	char — string	LR, SC, OAH	LR
<code>totalNumberOfReflection</code>	Reflection order	double	positive integer	2
<code>tdlTypeChannel</code>	Interpolation	char — string	Impulse, Sinc	Impulse

**Table A.6:** Tunable properties in `paaConfigNodeX.txt` if `chanModel = NIST`.

Parameter	Description	Data Type	Valid Range	Default
<code>numAntenna</code>	Number of antennas	double	positive integer	16
<code>Geometry</code>	Geometry	char — string	UniformLinear Uniform- Rectangular	Uniform- Rectangular
<code>numAntennaVert</code>	Number of vertical antennas	double	positive integer	4

**Table A.7:** Tunable properties of `chan` in `channelConfig.txt` if `chanModel = sensing`.

Parameter	Description	Data Type	Valid Range	Default
<code>Normalization</code>	Channel Normalization	char — string	'packet', 'none'	'packet'

# References

- [1] *Part 11: Wireless LAN (MAC) and (PHY) Specifications–Amendment 2: Enhanced Throughput for Operation in License-Exempt Bands Above 45 GHz*, IEEE Std. IEEE P802.11ay/D7.0, 2020.
- [2] *Part 11: Wireless LAN Medium Access Control (MAC) and Physical Layer (PHY) Specifications–Amendment 2: Enhancements for Wireless LAN Sensing*, IEEE Std. IEEE P802.11bf/D0.1, 2022.
- [3] H. Assasa *et al.* A Collection of Open-source Tools to Simulate IEEE 802.11ad/ay WLAN Networks in Network Simulator ns-3. [Online]. Available: <https://github.com/wigig-tools>
- [4] A. Bodi, S. Blandino, N. Varshney, J. Zhang, T. Ropitault, M. Lecci, P. Testolina, J. Wang, C. Lai, and C. Gentile, “A quasi-deterministic (Q-D) channel implementation in MATLAB software,” <https://github.com/wigig-tools/qd-realization>, 2021.
- [5] R. Boulic, N. M. Thalmann, and D. Thalmann, “A global human walking model with real-time kinematic personification,” *The visual computer*, vol. 6, no. 6, pp. 344–358, 1990.